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(54) **ENHANCED TRAVEL MODES FOR VEHICLES**

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**G05D 1/00** (2006.01)  
**G05D 1/02** (2020.01)  
**G08G 1/00** (2006.01)  
**B62D 15/02** (2006.01)

(52) **U.S. Cl.**

CPC ..... **G08G 1/161** (2013.01); **B62D 15/0255** (2013.01); **G05D 1/0011** (2013.01); **G05D 1/0088** (2013.01); **G05D 1/0212** (2013.01); **G05D 1/0297** (2013.01); **G08G 1/22** (2013.01); **B60W 2754/10** (2020.02); **G05D 2201/0213** (2013.01)

(58) **Field of Classification Search**

None  
See application file for complete search history.

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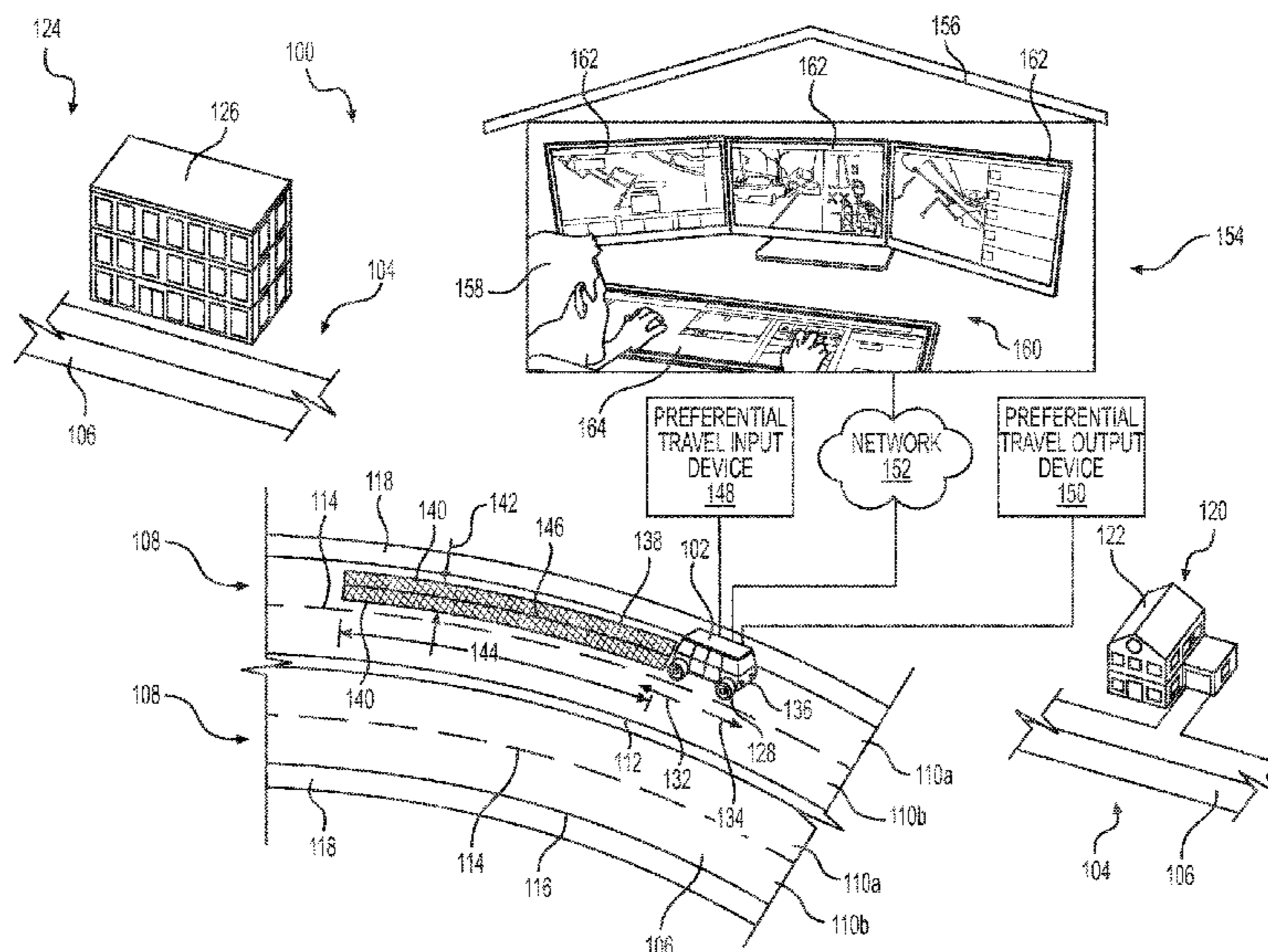
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(57) **ABSTRACT**

A method for operating a fleet of vehicles may include determining a first set of parameters for operating a first vehicle as it travels to a destination, and determining a second set of parameters for operating a second vehicle. Consumption of the first set of parameters by the first vehicle may cause the first vehicle to accelerate, alter shocks and/or suspensions, and/or move into a free lane. Consumption of the second set of parameters by the second vehicle may cause the second vehicle to remain outside of a drive envelope of the first vehicle, between the first vehicle and the particular destination.

**20 Claims, 8 Drawing Sheets**



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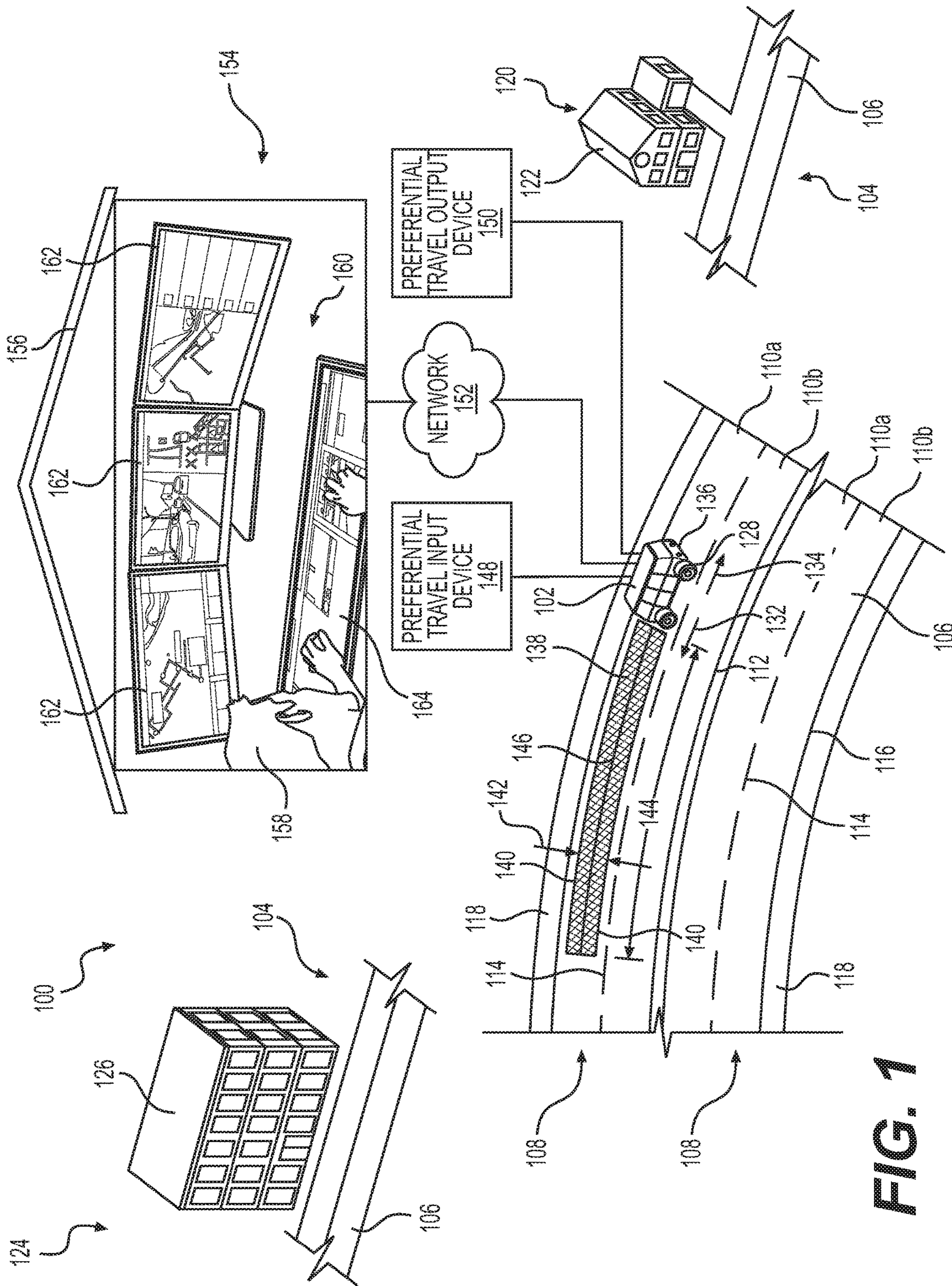
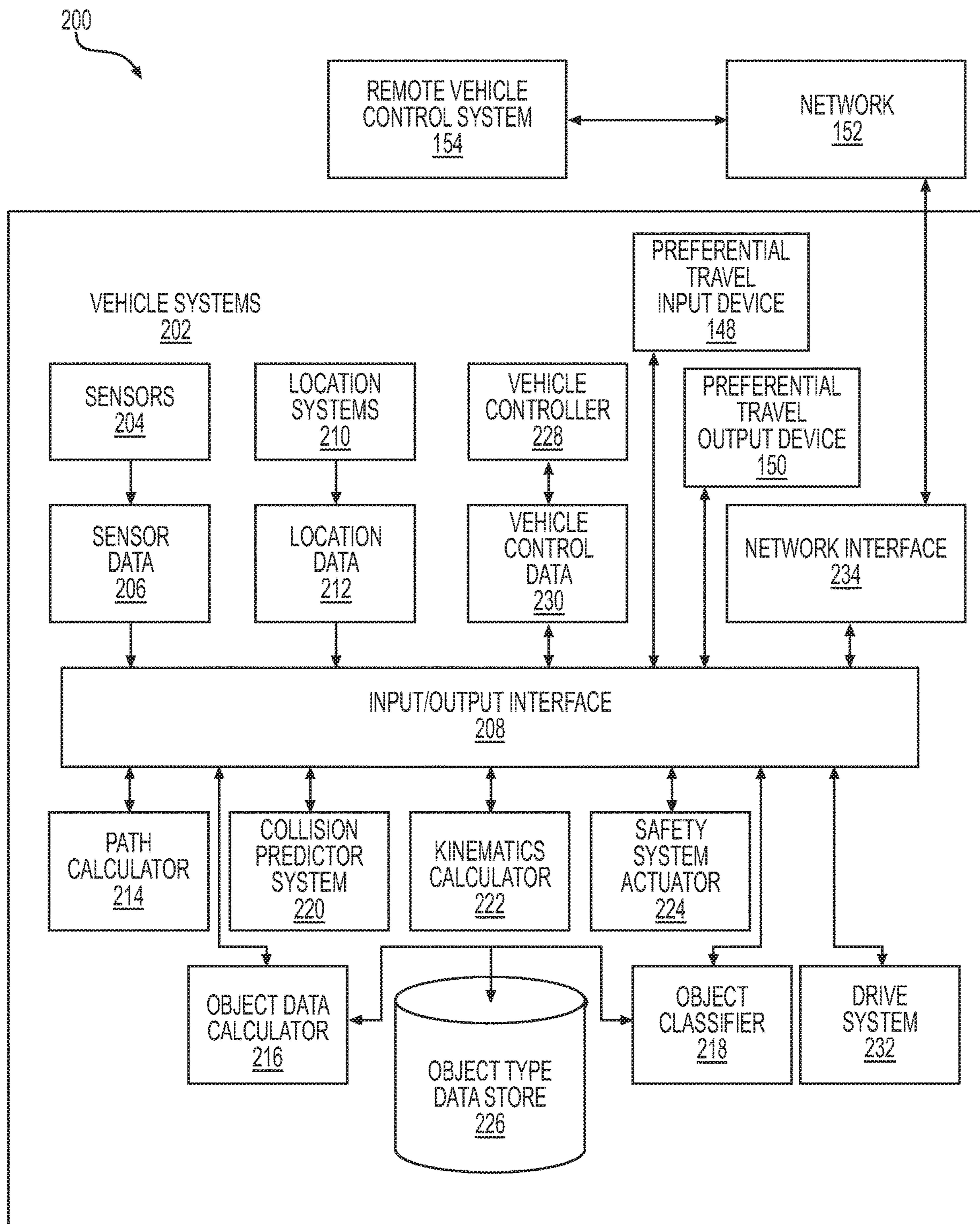


FIG. 1



**FIG. 2**

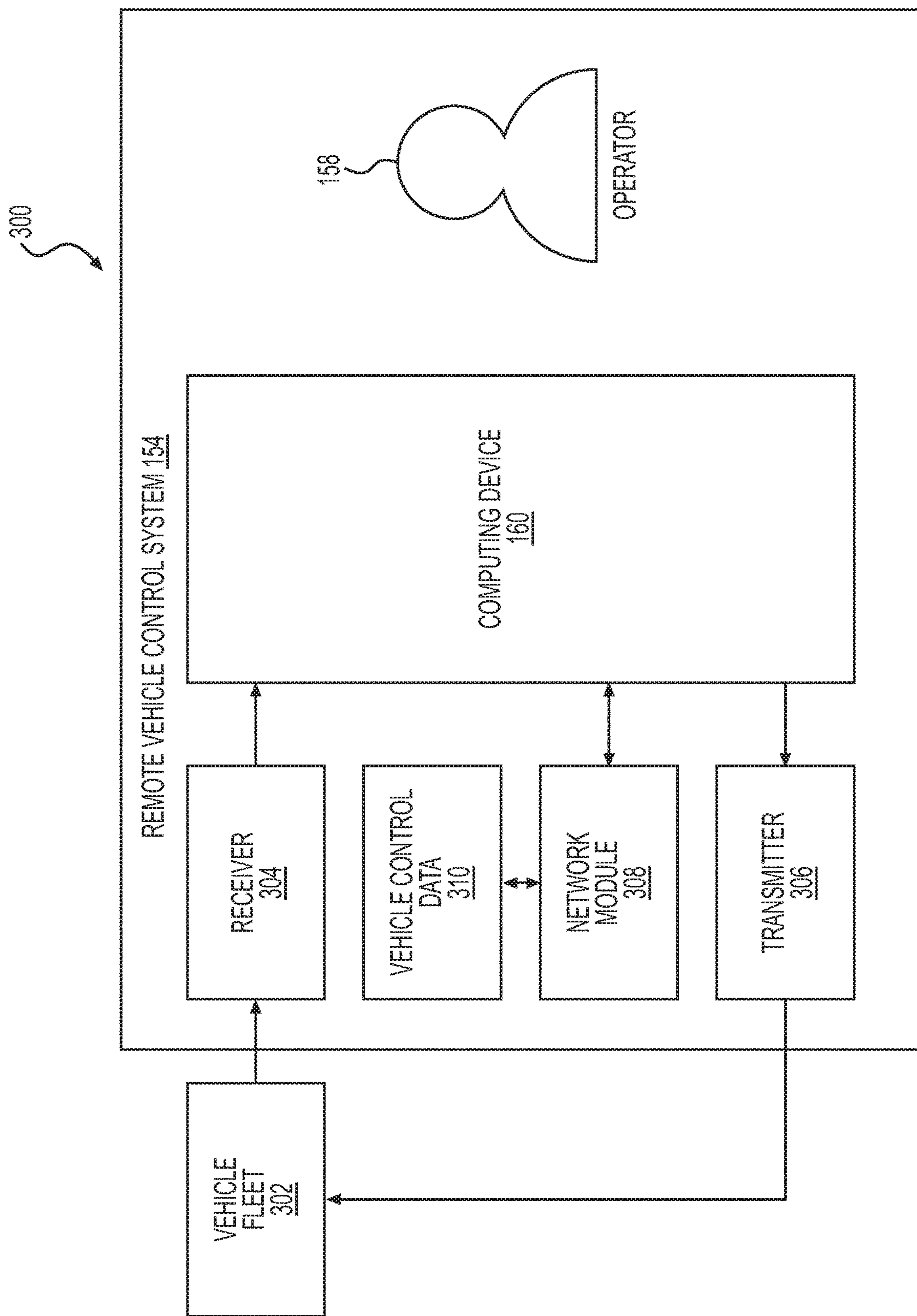
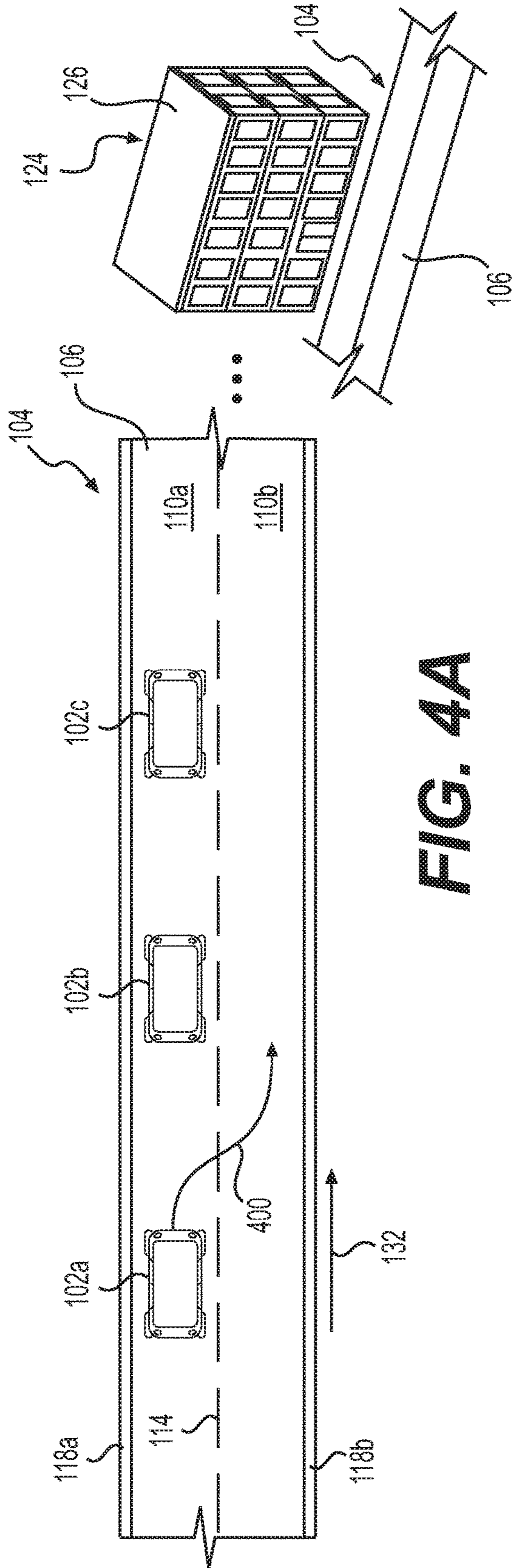
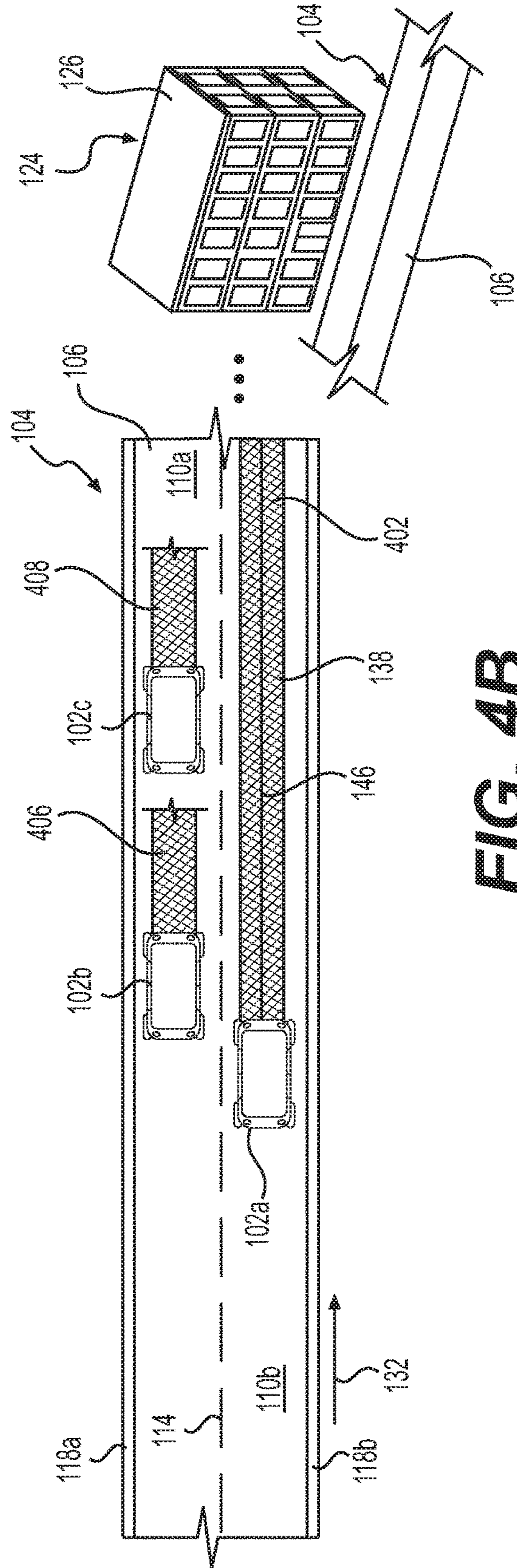


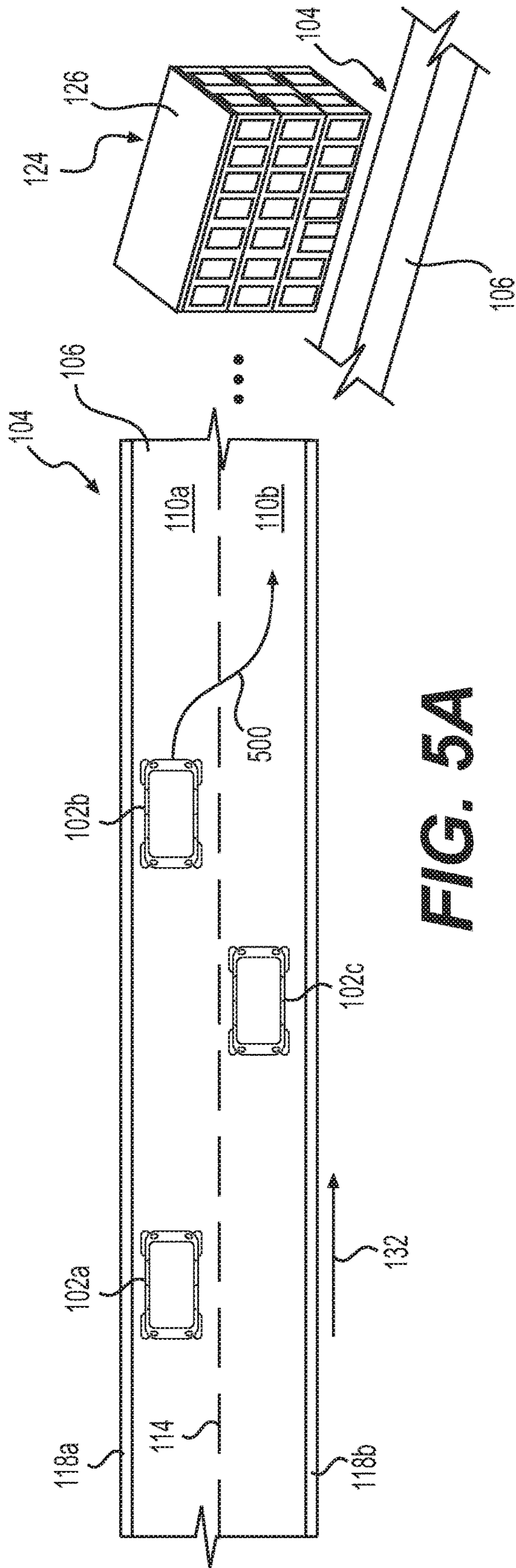
FIG. 3



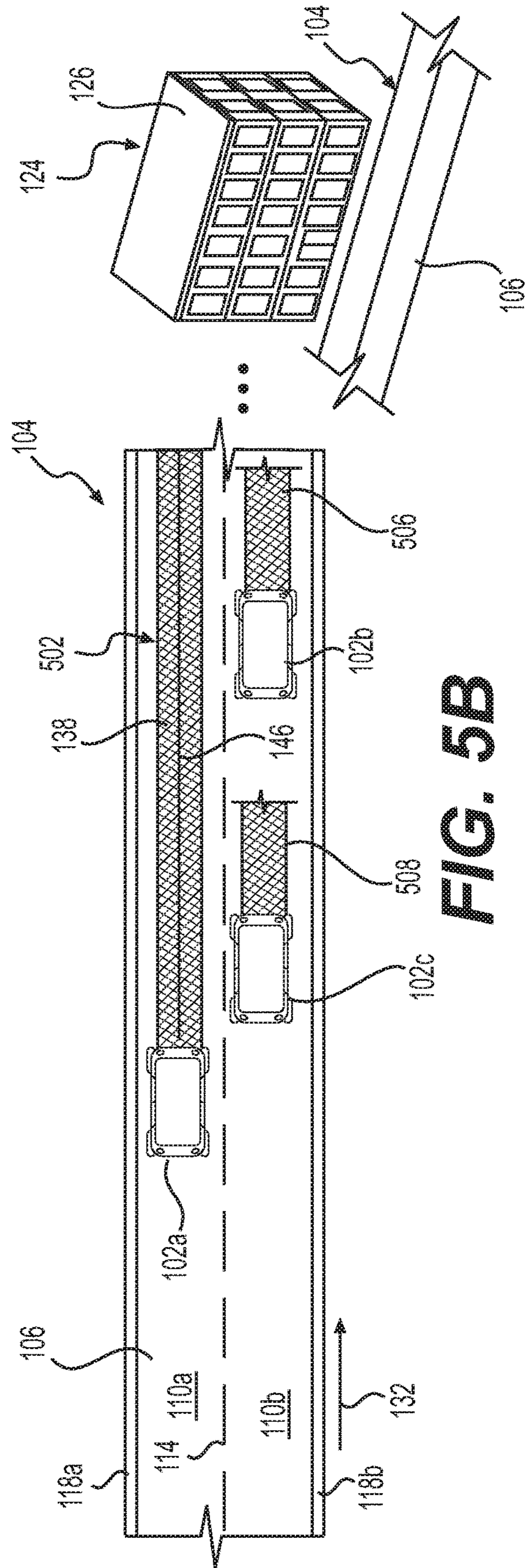
**FIG. 4A**



**FIG. 4B**



**FIG. 5A**



**FIG. 5B**

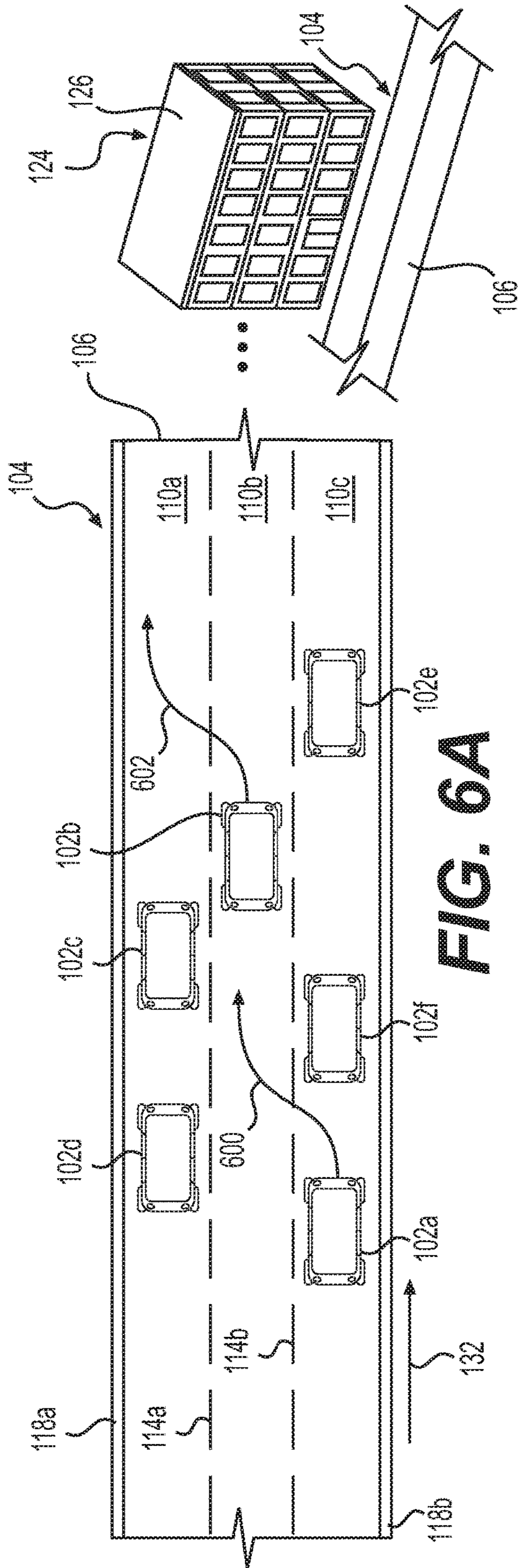


FIG. 6A

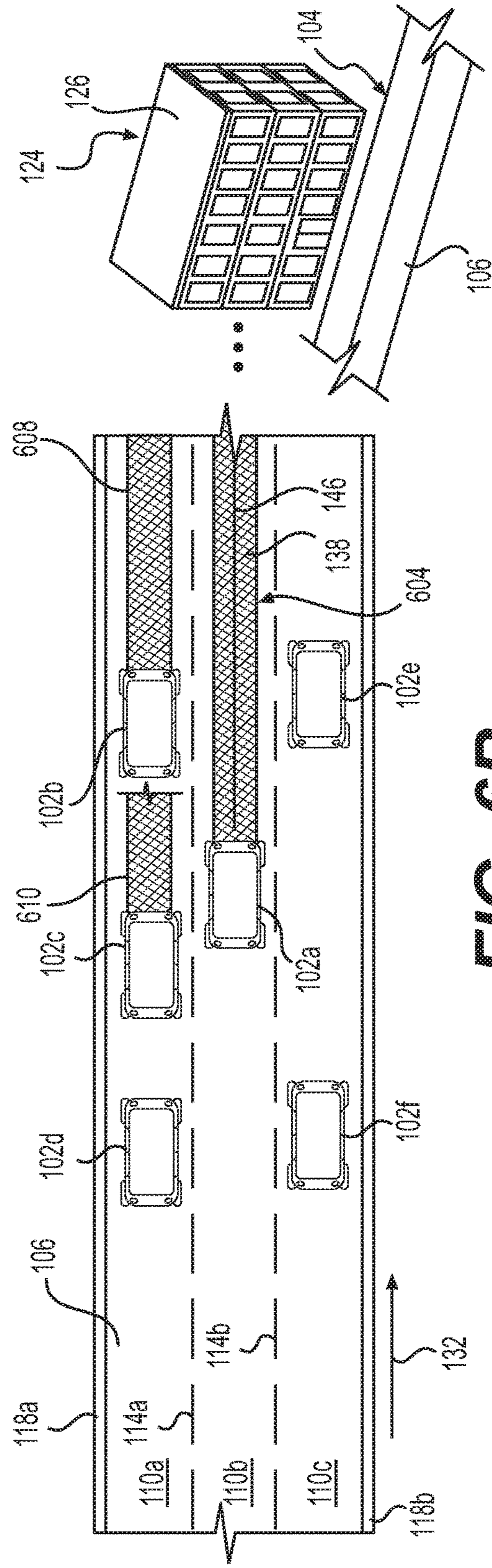
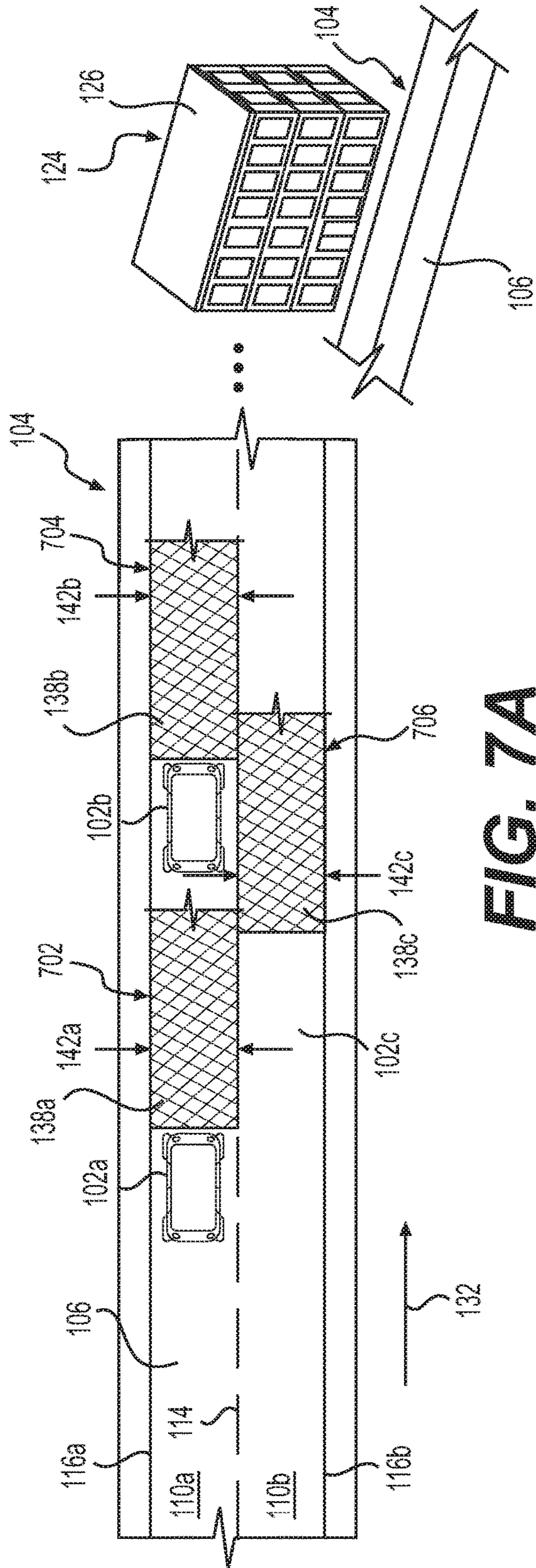
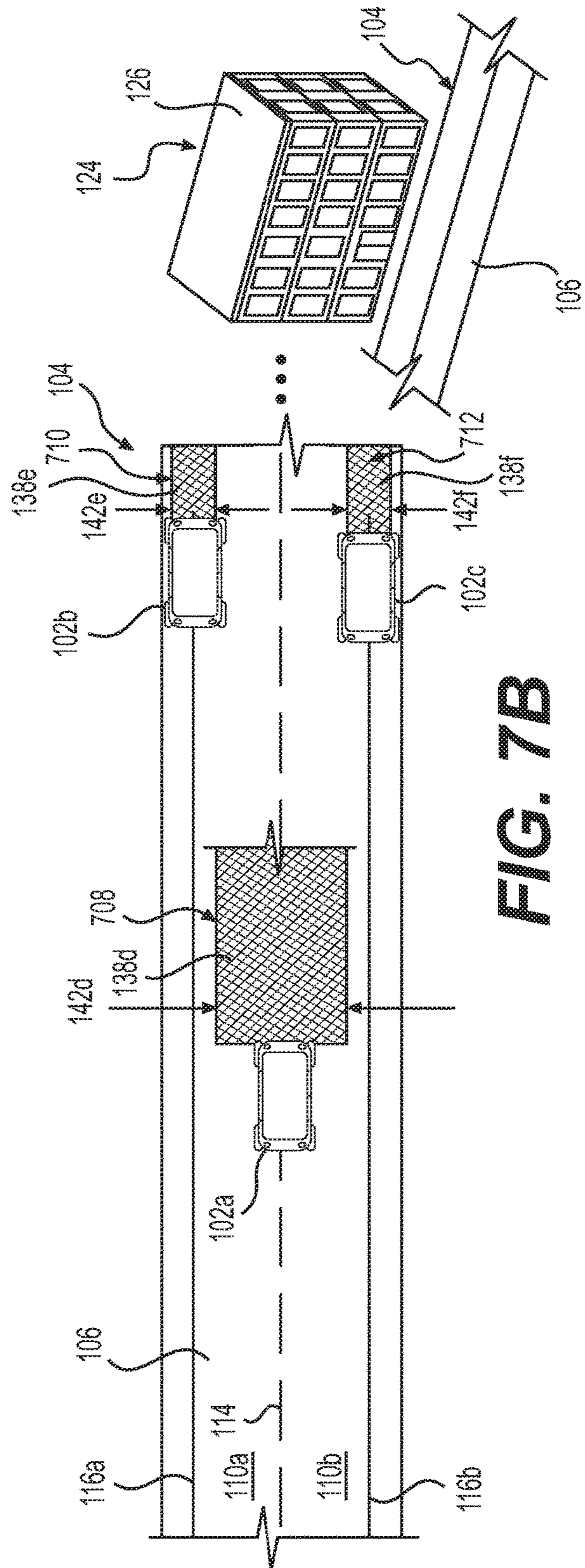


FIG. 6B



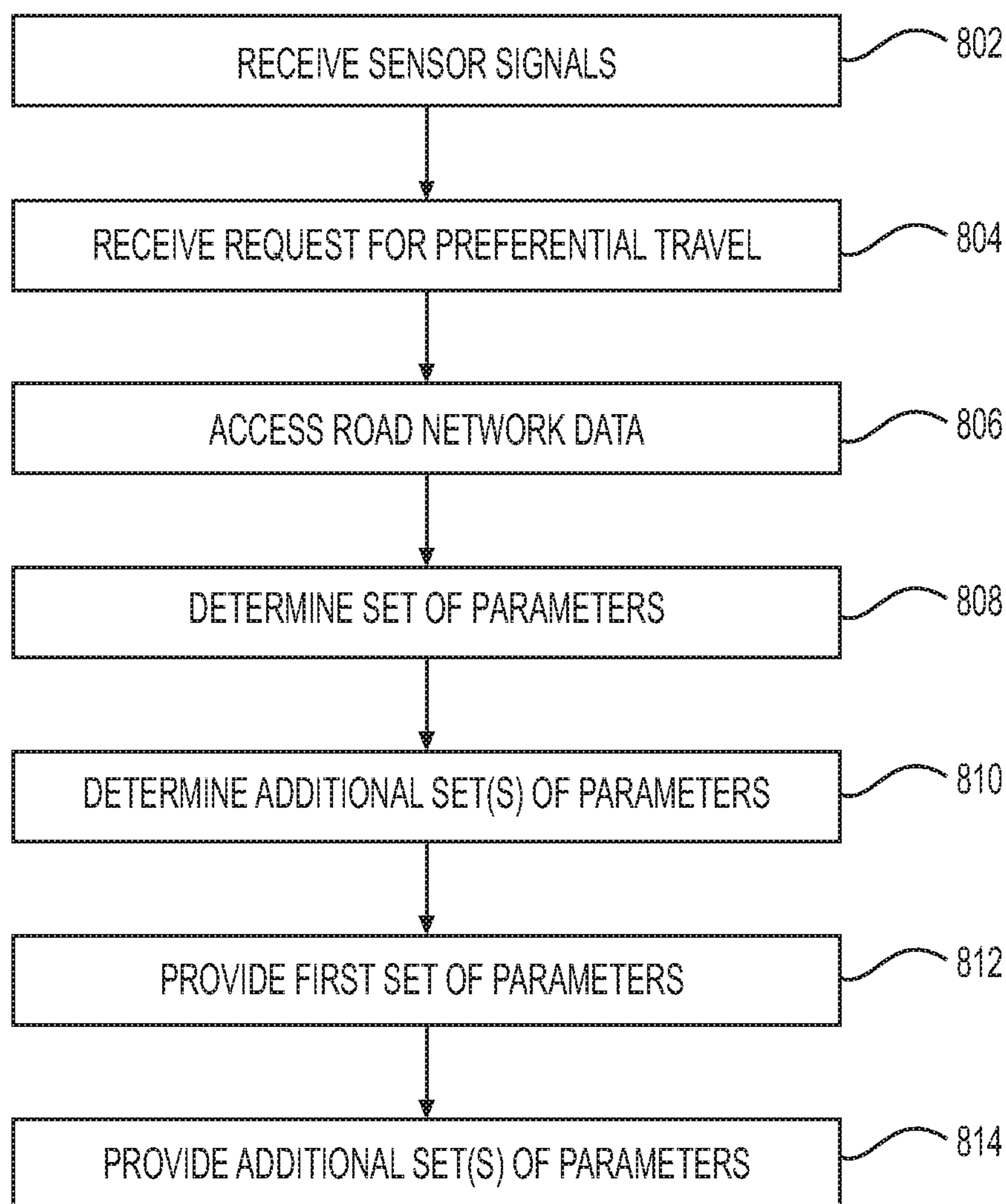


**FIG. 7A**



**FIG. 7B**

800



**FIG. 8**

## ENHANCED TRAVEL MODES FOR VEHICLES

This application claims priority to and is a continuation of U.S. patent application Ser. No. 15/727,234, filed on Oct. 6, 2017, the entire contents of which are incorporated herein by reference.

### BACKGROUND

Vehicles may be used to transport people between different locations. Normal driving procedures may include maneuvering the vehicle within the confines of a lane, maneuvering around turns in the road, safely passing through intersections, as well as complying with traffic laws. In most scenarios, all vehicles traveling on a road may be given equal priority in order to reach their respective destinations. In such scenarios, all vehicles may be controlled so as to maximize the efficiency of traffic flow on the road and/or on portions of a road network.

### BRIEF DESCRIPTION OF THE DRAWINGS

The detailed description is described with reference to the accompanying figures. In the figures, the left-most digit(s) of a reference number identify the figure in which the reference number first appears. The same reference numbers in different figures indicate similar or identical items.

FIG. 1 is a schematic diagram of an example environment through which an example vehicle travels along a road of a road network. As shown in FIG. 1, such a vehicle may include a preferential travel input device configured to enable a passenger of the vehicle to request a prioritized path or other preferential travel benefits when traveling to a particular destination.

FIG. 2 is a block diagram illustrating an example vehicle system architecture.

FIG. 3 is a block diagram illustrating an example vehicle control system architecture useful for interacting with vehicles remotely.

FIGS. 4a and 4b are schematic views of a portion of an example road network in which example vehicles are traveling along respective paths. In such examples, at least one of the vehicles may be traveling along a prioritized path to a particular destination.

FIGS. 5a and 5b are additional schematic views of a portion of an example road network in which example vehicles are traveling along respective paths.

FIGS. 6a and 6b are further schematic views of a portion of an example road network in which example vehicles are traveling along respective paths.

FIGS. 7a and 7b are still further schematic views of a portion of an example road network in which example vehicles are traveling along respective paths.

FIG. 8 is a flow diagram of an example method for operating one or more vehicles traveling in an example road network. Such an example method may include determining and providing one or more sets of parameters governing operation of one or more vehicles while the vehicles travel to respective destinations.

### DETAILED DESCRIPTION

This disclosure is generally directed to facilitating interaction between a vehicle, such as a driverless vehicle, a remotely located vehicle control system, one or more other vehicles, and/or one or more other devices (e.g., traffic

signals, signs, barriers, bridges, etc.). As mentioned above, such a vehicle traveling on a road of a road network, from a first location to a particular destination at a second location, may require or request preferential travel for a variety of reasons. For example, the vehicle and/or a passenger thereof may be part of a travel program or other premium service in which prioritized or preferential travel is a benefit. A passenger of the vehicle may also request preferential travel in emergency situations or in other time-sensitive situations. In such circumstances, for example, the passenger may provide a touch input, a voice input, a gesture input, and/or other input via a preferential travel input device of the vehicle. The preferential travel input device may be operably connected to a vehicle controller configured to process such an input, and to provide a signal indicative of such an input to the remotely located vehicle control system. The input may additionally or alternatively be provided to the vehicle controller by one or more applications operable on a mobile phone, tablet, laptop computer, or other electronic device, and in such examples, such electronic devices may comprise a preferential travel input device. In still further examples, such preferential travel may be a preset user setting and/or a subscription-based service associated with the vehicle and/or the user. In such examples, the vehicle may automatically be granted preferential travel once the passenger enters the vehicle and/or once the vehicle is turned on. Additionally, the passenger may be granted preferential travel upon paying a subscription fee and/or upon paying a one-time fee upon requesting preferential travel.

As will be described in greater detail below, during normal operations, the vehicle may travel and/or otherwise operate according to a set of nominal operating parameters or parameters, and such operating parameters may be adjusted if preferential travel is requested by a passenger of the vehicle. For example, upon receiving a request from the passenger, the vehicle controller may provide a signal indicative of a request for preferential travel to the remote vehicle control system via one or more wireless networks. Based at least partly on such a request, the remote vehicle control system may determine a set of parameters that includes modifications to the nominal operating parameters currently governing operation of the vehicle from which the request for preferential travel originated (e.g., a “requesting vehicle”). Such a set of modified parameters may include, for example, a new/modified speed threshold below which the requesting vehicle may be permitted and, in some situations, required to operate, a new/modified drive line along which the requesting vehicle may be permitted and, in some situations, required to travel, a new/modified drive envelope along which or within which the requesting vehicle may be permitted and, in some situations, required to travel, new/modified traffic rules (e.g., rules governing vehicle operation with regard to stop signs, traffic lights, no passing zones, school zones, or other areas) with which the requesting vehicle must abide, and/or other new/modified rules or limitations for operating the requesting vehicle within the road network.

In some examples, the set of parameters may include road network data and/or other information that may be used by a vehicle controller of the requesting vehicle to generate a drive envelope that defines a prioritized path along which the requesting vehicle may travel between the vehicle’s current location in the road network to the desired destination. Alternatively, such a set of new/modified parameters may identify, define, and/or include such a prioritized path. Such a prioritized path may include a path in which none of the additional vehicles, or a limited number of additional

vehicles, in the road network are disposed within a drive envelope of the requesting vehicle as the requesting vehicle travels to the destination. In some examples, the prioritized path may be selected and/or otherwise determined based at least in part on the fact that no other vehicles are present within such a drive envelope. Additionally or alternatively, the additional vehicles in the road network may be actively controlled to avoid the trajectory of the requesting vehicle. In such examples, the signal provided to the remote vehicle control system by the vehicle controller may include sensor information and/or other information indicative of the requesting vehicle's current location. The signal may also include an address, global positioning coordinates, and/or other indication of the desired destination. The signal may further include an identifier uniquely identifying the requesting vehicle, an additional identifier uniquely identifying one or more passengers of the requesting vehicle, and/or other information related to the request. Further, in any of the examples described herein, such a "drive envelope" may be defined as a preferred area on which the vehicle should drive to reach a destination having an extent along a direction of travel associated with a distance the vehicle may traverse in a fixed period of time (e.g., according to a receding horizon technique) or a specified finite distance. For example, such a drive envelope may extend a length along a drive segment, line, and/or route along which the requesting vehicle may be controlled to travel for approximately 10 seconds. Alternatively, such a drive envelope may extend a fixed distance, e.g. 500 feet, in the direction of a line and/or route along which the requesting vehicle may be controlled to travel. Such a "drive envelope" may comprise a drive line indicating an ideal line for the vehicle to follow within the drive envelope. As used herein, a trajectory may be a selected subset of the "drive envelope" in which the vehicle actually traverses, or is selected to traverse. It is understood that the finite period of time and finite distance noted above are merely examples and, in further embodiments, such finite periods of time and finite distances may be greater than or less than those noted above.

In such examples, and based at least in part on the request, one or more computing devices of the remote vehicle control system may determine a first set of parameters associated with the requesting vehicle as well as one or more additional sets of parameters associated with the remaining vehicles in the road network. The first set of parameters may require that the requesting vehicle travel along a prioritized path from the vehicle's current location to the particular destination. Such a prioritized path may be configured such that none of the additional vehicles in the road network are disposed within one or more drive envelopes (e.g., a series of consecutive drive envelopes) of the requesting vehicle as the requesting vehicle travels to the destination. The additional sets of parameters may require that the remaining vehicles in the road network remain outside of the prioritized path of the requesting vehicle. For example, a second set of parameters provided to a second vehicle traveling in the road network may require that the second vehicle remain outside of the trajectory of the requesting vehicle as the requesting vehicle travels to a destination. Further, in some examples the signal sent to the remote vehicle control system by the requesting vehicle may identify an area, zone, radius, and/or other location that is to be avoided by the additional vehicles in the road network (e.g., a temporary non-entry zone) when the requesting vehicle is disposed proximate and/or within such a location. In such examples, such locations may be identified in the one or more additional sets of parameters determined by the remote vehicle control system.

Additionally, while some embodiments of the present disclosure relate to centralized control examples in which signals are provided to a remote vehicle control system and in which the remote vehicle control system determines one or more sets of parameters based at least in part on such signals, in other embodiments, such a remote vehicle control system may be omitted. For example, in additional decentralized control embodiments the vehicle controller of the requesting vehicle may provide a signal indicative of a request for preferential travel to the respective vehicle controllers of one or more of the additional vehicles located in the road network via the one or more wireless networks. In such embodiments, the vehicle controller of the requesting vehicle may determine a first set of parameters including, among other things, a prioritized path for the requesting vehicle to travel along. As noted above, such a prioritized path may include one or more drive envelopes and/or trajectories, and none of the additional vehicles may be disposed within or along such drive envelopes and/or trajectories as the requesting vehicle travels along the prioritized path to the destination. Additionally, based at least partly on such a request, the vehicle controllers of the additional vehicles may determine additional respective sets of parameters for operating the corresponding vehicles. Such additional sets of parameters require that each of the additional vehicles remain outside of the one or more trajectories of the prioritized path as the requesting vehicle travels to the destination. In some examples, one or more of the additional vehicles and/or owners or passengers of the additional vehicles may be compensated for operating in accordance with such additional respective sets of parameters and/or for otherwise facilitating the preferential travel of the requesting vehicle. For example, as part of requesting preferential travel and/or as a requirement for being granted preferential travel, a passenger of the requesting vehicle may pay a corresponding fee. In such examples, at least a portion of the fee may be distributed to an owner or passenger of one or more of the remaining vehicles within the road network whose travel is hindered, de-prioritized and/or otherwise affected by the requesting vehicle being granted preferential or prioritized travel. The techniques and systems described herein may be implemented in a number of ways. Example implementations are provided below with reference to the figures.

FIG. 1 is a schematic diagram of an example environment 100 through which an example vehicle 102 travels. The example environment 100 includes a road network 104 including a plurality of example roads 106 having two pairs 108 of lanes 110a, 110b separated by a median or double-yellow line 112. For example, a first lane 110a, a second lane 110b, and/or one or more additional lanes may be at least partially defined by a lane dividing line 114 and/or a lane boundary line 116. The example road 106 also includes shoulders 118 located on opposite sides of the road 106. FIG. 1 also shows an example geographic location 120 associated with a departure location including a structure 122, such as a house or building, and an example destination 124 also including a structure 126, such as a house or building. The road network 104 provides a number of roads 106 defining a path between the geographic location 120 and the destination 124, and FIG. 1 shows an enlarged view of a portion of an example road 106. The road network 104 may include a number of features, such as curves, intersections with cross-roads, crosswalks, traffic signs, traffic lights, railroad crossings, bridges, traffic circles, directional arrows, etc.

As shown in FIG. 1, the example vehicle 102 may travel through the example environment 100 via the road network

**104** according to a path extending from the geographic location **120** to the particular destination **124**. For the purpose of illustration, the vehicle **102** may be a driverless vehicle, such as an autonomous vehicle configured to operate according to a Level 5 classification issued by the U.S. National Highway Traffic Safety Administration, which describes a vehicle capable of performing all safety-critical functions for the entire trip, with the driver (or occupant) not being expected to control the vehicle at any time. In that case, since the vehicle **102** may be configured to control all functions from start to completion of the trip, including all parking functions, it may not include a driver. This is merely an example, and the systems and methods described herein may be incorporated into any ground-borne, airborne, or waterborne vehicle, including those ranging from vehicles that need to be manually controlled by a driver at all times, to those that are partially or fully autonomously controlled.

The example vehicle **102** shown in FIG. 1 is an automobile having four wheels **128** and respective tires for each of the wheels **128**. Other types and configurations of vehicles are contemplated, such as, for example, vans, sport utility vehicles, cross-over vehicles, trucks, buses, agricultural vehicles, and construction vehicles. The vehicle **102** may be powered by one or more internal combustion engines, one or more electric motors, hydrogen power, any combination thereof, and/or any other suitable power sources. In addition, although the example vehicle **102** has four wheels **128**, the systems and methods described herein may be incorporated into vehicles having fewer or a greater number of wheels, tires, and/or tracks. The example vehicle **102** has four-wheel steering and may operate generally with equal performance characteristics in all directions, for example, such that a first end **130** of the vehicle **102** is the front end of the vehicle **102** when travelling in a first direction **132**, and such that the first end **130** becomes the rear end of the vehicle **102** when traveling in the opposite, second direction **134**, as shown in FIG. 1. Similarly, a second end **136** of the vehicle **102** is the front end of the vehicle **102** when travelling in the second direction **134**, and such that the second end **136** becomes the rear end of the vehicle **102** when traveling in the opposite, first direction **132**. These example characteristics may facilitate greater maneuverability, for example, in small spaces or crowded environments, such as parking lots and urban areas.

In the example shown in FIG. 1, and as will be explained in greater detail below, the vehicle **102** may use various sensors and a vehicle controller to autonomously operate through the environment **100** along a path via the road network **104**. For example, the vehicle controller may be configured to determine a drive envelope **138** defined by virtual boundaries **140** within which the vehicle **102** may travel. For example, the drive envelope **138** may have a variable envelope width **142** in the width direction of the vehicle **102**, and a variable envelope length **144** extending in the direction of travel of the vehicle **102**. In some examples, the virtual boundaries **140** of the drive envelope **138** may be determined based at least in part on sensor data received from sensors associated with the vehicle **102** and/or road network data received by the vehicle **102** via a road network data store, as explained in more detail herein. In some examples, the vehicle **102** may travel along a drive line **146** within the drive envelope **138**. In such examples, the drive line **146** may extend approximately centrally through the drive envelope **138**, and the drive envelope **138** may define at least part of the path along which the vehicle **102** travels to reach the particular destination **124**. For example, the path along which the vehicle **102** travels may be approximately as wide as the vehicle **102** and/or the envelope width **142**. In

some examples, the drive line **146** may be, or may be used to determine, a trajectory along which the vehicle **102** may follow to achieve the desired path. Such a trajectory may be determined by, substantially simultaneously, generating a plurality of trajectories and selecting one of the trajectories which is best able to achieve the path. In such examples, the trajectory may be calculated in accordance with a receding horizon technique such that the trajectory only provides commands for a particular time window (e.g. less than 10 seconds) and is recalculated at a certain frequency (e.g. 10 Hz, 30 Hz, etc.).

The vehicle **102** may also include a preferential travel input device **148** and a preferential travel output device **150**. Shown schematically in FIG. 1, the preferential travel input device **148** and the preferential travel output device **150** may comprise separate respective devices or components of the vehicle **102**. Alternatively, the preferential travel input device **148** and the preferential travel output device **150** may comprise a single input/output device. The preferential travel input device **148** may be configured to assist a passenger with requesting preferential travel to the destination **124** and, in particular, with requesting a set of parameters governing operation of the vehicle **102** as the vehicle travels to the destination **124**. Such a set of parameters may include, for example, road network data, global positioning information, traffic rules, and/or other information that may be utilized as inputs to a vehicle controller of the vehicle **102**. In such examples, the vehicle controller of the vehicle **102** may generate and/or otherwise determine a drive envelope including a drive line **146**. As noted above, in any of the examples described herein, such a drive line **146** may be, or may be used to determine, one or more trajectories (e.g., a series of consecutive trajectories) along which the vehicle **102** may travel. In this way, the drive line **146** and/or the one or more trajectories may define a prioritized path extending from the vehicle **102** to the destination **124**. In additional examples, the set of parameters may define and/or otherwise include a drive envelope that includes and/or otherwise defines the prioritized path.

In some examples, the preferential travel input device **148** may comprise a button, switch, knob, lever, or other component of the vehicle **102** configured to receive a manual, physical, or touch input from a passenger. Such a preferential travel input device **148** may also comprise one or more touch screen displays, physical keyboards, virtual keyboards (e.g., a keyboard displayed via a touch screen or other display device), or other user interface devices of the vehicle **102** configured to receive such input. In still further examples, the preferential travel input device **148** may comprise one or more microphones configured to receive voice commands or other audible input from the passenger, and/or one or more cameras configured to receive visual or gesture input. In such examples, the vehicle controller may include voice recognition functionality, gesture recognition functionality, or other such capabilities in order to process inputs received via the preferential travel input device **148**. In any of the examples described herein, the preferential travel output device **150** may comprise a speaker, a display (e.g., a touch screen display), a heads-up display, and/or other such device configured to display, announce, and/or otherwise output at least part of a prioritized path along which the vehicle **102** may travel. The preferential travel output device **150** may include any of the components described above with respect to the preferential travel input device **148**. The preferential travel input device **148** and the preferential travel output device **150** may be operably and/or otherwise connected to the vehicle controller of the vehicle

102. It is also understood that such inputs and/or outputs may be provided by one or more applications operable on a mobile phone, tablet, laptop computer, or other electronic device that are in communication (wirelessly or otherwise) with the vehicle 102, and in such examples, such electronic devices may comprise a preferential travel input device 148 and/or a preferential travel output device 150.

In some examples, the preferential travel input device 148 may be configured to receive an input from a passenger of the vehicle 102 indicative of a request for preferential travel, and the preferential travel input device 148 may be configured to generate and/or send a signal to the vehicle controller of the vehicle 102 containing information indicative of the request, at least partly in response to such an input. In such examples, the vehicle controller of the vehicle 102 may be communicatively and/or otherwise connected to a network 152, and the vehicle controller may provide a corresponding signal and/or request to a remote vehicle control system 154 via the network 152. In any of the examples described herein, a request for preferential travel may comprise a request for a prioritized drive envelope and/or path extending from the vehicle 102 to a particular destination 124 that is accessible via the road network 104 on which the vehicle 102 is traveling. In response, the vehicle controller of the vehicle 102 may request assistance from the remote vehicle control system 154 and, in particular, may request the determination of a set of modified parameters governing operation of the vehicle 102 as the vehicle 102 travels to the particular destination 124. Such a set of modified parameters may include, for example, an alteration of at least one of the nominal operating parameters currently governing operation of the vehicle 102. In another example, such a set of modified parameters may include at least one additional operating parameter not included in the nominal operating parameters. In a further example, such a set of modified parameters may omit one or more of the nominal operating parameters. In some examples, the vehicle 102 may be a part of a fleet of vehicles in communication with the remote vehicle control system 154 via the network 152. In such examples, the signal provided by the vehicle controller of the vehicle 102 may include sensor information and/or other information indicative of a current location of the vehicle 102. The signal may also include an address, global positioning coordinates, and/or other indication of the desired destination 124, and such information may be provided by the passenger via the preferential travel input device 148. The signal may further include an identifier uniquely identifying the requesting vehicle 102, an additional identifier uniquely identifying one or more passengers of the requesting vehicle 102, and/or other information related to the request.

As will be explained in further detail below, at least partly in response to such a request, the remote vehicle control system 154 may determine a first set of modified parameters governing operation of the vehicle 102. The first set of modified parameters may include a modified (e.g., prioritized) drive envelope 138 comprising a modified (e.g., prioritized) drive line 146. As noted above, such a drive line 146 may comprise one or more trajectories (e.g., a series of consecutive trajectories) defining a prioritized path from the vehicle 102 to the destination 124. In any of the examples described herein, the first set of modified parameters may include road network data and/or other information that may be used by the vehicle controller of the vehicle 102 to determine such a drive envelope and/or prioritized path. For example, the first set of modified parameters may also identify portions of the road network 104 which may or may

not be used by the requesting vehicle 102 as the vehicle 102 travels to the destination 124. At least partly in response to such a request, the remote vehicle control system 154 may also determine a second set of modified parameters governing operation of a second vehicle of the fleet of vehicles. Such a second set of parameters may include a modified (e.g., a reduced priority) drive envelope 138 comprising a modified (e.g., a reduced priority) drive line 146. Such a drive line 146 may comprise one or more trajectories (e.g., a series of consecutive trajectories) defining a second path (e.g., a path of reduced priority) along which the second vehicle of the fleet of vehicles travels such that the vehicle 102 providing the request may have priority in reaching the destination 124 along the road network 104. Alternatively, the second set of parameters may include road network data and/or other information that may be used by the vehicle controller of the second vehicle to determine such a second path (e.g., by rerouting the second vehicle to take alternate routes allowing the vehicle 102 to have less traffic on the prioritized route). In such examples, the second set of parameters may be at least partly more restrictive than the first set of parameters. For example, in accordance with the second set of parameters, the second vehicle and/or a remainder of the plurality of vehicles may be permitted and, in some situations, required to clear at least one of the first lane 110a or the second lane 110b of the road 106 such that the vehicle 102 providing the request may travel along a prioritized path (i.e., a travel path in which none of the additional vehicles in the road network are disposed within the drive envelope or along one or more trajectories of the requesting vehicle 102 as the requesting vehicle 102 travels to the particular destination 124. In any of the examples described herein, one or more of the vehicles 102 may form a caravan and/or a motorcade as the vehicles 102 travel together in the road 106. Further, in any of the examples described herein, one or more of the vehicles 102 may include an input/output interface or other component that enables dynamic short range communication between the respective vehicles 102. For example, such components may enable a first vehicle 102 to communicate a first set of modified parameters, a prioritized drive envelope 138, a prioritized drive line 146, one or more trajectories, a prioritized path, and/or any other information described herein to one or more additional vehicles 102 traversing the road network 104 having corresponding input/output interface components. Such additional vehicles 102 may also be configured to communicate information back to the first vehicle 102, using the corresponding input/output interface components, in response to information received from the first vehicle 102.

In some examples, and as shown schematically in FIG. 1, the remote vehicle control system 154 may be located at a remote control center 156, and one or more human operators 158 may also be located at the remote control center 156 in order to operate the remote vehicle control system 154. In some examples, one or more of the operators 158 may not be human. For example, they may be computer systems leveraging artificial intelligence, machine learning, and/or other decision making strategies in order to operate the remote vehicle control system 154. In the example shown, the operator 158 may interact with one or more vehicles 102 in the fleet of vehicles via an operator computing device 160. The operator computing device 160 may include one or more displays 162 configured to provide the operator 158 with data related to operation of the vehicle 102, a subset of the fleet of vehicles, and/or the fleet of vehicles. For example, the display(s) 162 may be configured to show data

related to sensor signals received from the vehicles **102**, data related to the road network **104**, requests for preferential travel received from the vehicles **102**, and/or additional data or information to facilitate providing travel paths, vehicle information, directions, and/or other information or assistance to the vehicles **102**. In addition, the operator computing device **160** may include an operator input device **164** configured to allow the operator **158** to provide information to one or more of the vehicles **102**, for example, in the form of signals providing guidance to the vehicles **102**. The operator input device **164** may include one or more of a touch-sensitive screen, a stylus, a mouse, a dial, a keyboard, a keypad, and/or a gesture-input system configured to translate gestures performed by the operator **158** into input commands for the computing device **160**. As explained in more detail below, the remote vehicle control system **154** may provide one or more of the vehicles **102** with a set of modified parameters that may be used by the local vehicle controllers of the respective vehicles **102** to govern operation of the respective vehicle **102**. It is understood, however, that any of the methods and/or operations described herein with respect to the remote vehicle control system **154** may be performed by one or more of the respective vehicle controllers of the vehicles **102** traversing the road network **104**. In such examples, the remote vehicle control system **154** may be omitted and, for example, the various sets of parameters, drive envelopes, paths, drive lines, trajectories, and/or other operational parameters described herein may be determined and/or provided by at least one of the vehicle controllers.

FIG. **2** is a block diagram of an example architecture **200** including vehicle systems **202** for controlling operation of the systems that provide data associated with operation of the vehicle **102**, and that control operation of the vehicle **102**. Any of the components described with respect to FIG. **2** may be incorporated into one or more of the vehicles **102** described herein.

In various implementations, the architecture **200** may be implemented using a uniprocessor system including one processor, or a multiprocessor system including several processors (e.g., two, four, eight, or another suitable number). The processor(s) may be any suitable processor capable of executing instructions. For example, in various implementations, the processor(s) may be general-purpose or embedded processors implementing any of a variety of instruction set architectures (ISAs), such as the x86, PowerPC, SPARC, or MIPS ISAs, or any other suitable ISA. In multiprocessor systems, each processor may commonly, but not necessarily, implement the same ISA. In some examples, the processor(s) may include a central processing unit (CPU), a graphics processing unit (GPU), or a combination thereof. The processor(s) may comprise a component of the vehicle controller described herein. In some examples, the processor(s) may include one or more field-programmable gate arrays, application-specific integrated circuits, microprocessors, and/or other processor components.

The example architecture **200** may include a non-transitory computer readable media configured to store executable instructions/modules, data, and/or data items accessible by the processor(s). In various implementations, the non-transitory computer readable media may be implemented using any suitable memory technology, such as static random access memory (SRAM), synchronous dynamic RAM (SDRAM), nonvolatile/Flash-type memory, or any other type of memory. In the illustrated implementation, program instructions and data implementing desired functions, such as those described above, are shown stored within the

non-transitory computer readable memory. In other implementations, program instructions, and/or data may be received, sent, or stored on different types of computer-accessible media, such as non-transitory media, or on similar media separate from the non-transitory computer readable media. Generally, a non-transitory, computer readable memory may include storage media or memory media, such as flash memory (e.g., solid state memory), magnetic or optical media (e.g., a disk) coupled to the architecture **200** via an I/O interface. Program instructions and data stored via a non-transitory computer readable medium may be transmitted by transmission media or signals such as electrical, electromagnetic, or digital signals, which may be conveyed via a communication medium such as a network and/or a wireless link, such as may be implemented via a network interface.

In some implementations, the I/O interface may be configured to coordinate I/O traffic between the processor(s), the non-transitory computer readable media, and any peripheral devices, the network interface, or other peripheral interfaces, such as input/output devices. In some implementations, the I/O interface may perform any necessary protocol, timing, or other data transformations to convert data signals from one component (e.g., the non-transitory computer readable media) into a format suitable for use by another component (e.g., processor(s)). In some implementations, the I/O interface may include support for devices attached through various types of peripheral buses, such as a variant of the Peripheral Component Interconnect (PCI) bus standard or the Universal Serial Bus (USB) standard, for example. In some implementations, the function of the I/O interface may be split into two or more separate components, such as a north bridge and a south bridge, for example. Also, in some implementations, some or all of the functionality of the I/O interface, such as an interface to the non-transitory computer readable media, may be incorporated directly into the processor(s).

In the example architecture **200** shown in FIG. **2**, the example vehicle systems **202** include a plurality of sensors **204**, for example, configured to sense movement of the vehicle **102** through the environment **100**, sense environmental data, such as the ambient temperature, pressure, and humidity, and/or sense objects in the environment **100** surrounding the vehicle **102**. In some examples, the sensors **204** may include sensors configured to identify a location on a map (e.g., a geographic location of the vehicle **102**). The sensors **204** may include, for example, one or more light detection and ranging sensors (LIDAR), one or more cameras, one or more radio detection and ranging sensors (RADAR), one or more sound navigation and ranging sensors (SONAR) (e.g., ultrasonic transducers), one or more microphones for sensing sounds in the environment **100**, such as sirens from law enforcement and emergency vehicles, and other sensors related to the operation of the vehicle **102**. Other sensors may include a speed sensor, sensors related to operation of internal combustion engines and/or electric motors, sensors related to the tires to detect tire temperature, tire pressure, and tread depth, and/or brake-related sensors for detecting brake temperatures and/or wear, and in vehicles having regenerative braking, sensors for detecting parameters related to operation of the regenerative braking system. The sensors **204** may also include, for example, inertial measurement units (IMUs), accelerometers, and gyroscopes. The sensors **204** may be configured to provide sensor data **206** representative of the sensed objects and signals to the vehicle systems **202** via, for example, an input/output (I/O) interface **208**. Other types of sensors and

sensor data are contemplated. As noted above, in some examples one or more of the I/O interfaces **208** described herein, and/or the vehicle system **202** generally, may include an antenna, transmitter, transceiver, and/or other components configured to enable dynamic short range communication between the vehicles **102**. In particular, such components may enable the transfer of signals and/or information between the vehicles **102** as the vehicles traverse the road network **104**.

The example vehicle systems **202** also include location systems **210** configured to receive location information, including position and orientation data (e.g., a local position or local pose (e.g., a location and orientation)) from the sensors **204** and/or external sources, and provide location data **212** to other portions of the vehicle systems **202** via the I/O interface **208**. The external sources may include global satellites for facilitating operation of a global positioning system (GPS) and/or a wireless network for communicating and receiving information related to the vehicle's location, such as map data. The location systems **210** may also include sensors configured to assist with navigation of the vehicle **102**, such as wheel encoders for sensing the rotation of the wheels **128**, inertial navigation sensors, such as gyroscopes and/or accelerometers, and/or cameras for obtaining image data for dead-reckoning navigation (e.g., visual odometry), a Bayesian filtering schema (e.g. SLAM), bundle adjustment, or the like.

The example vehicle systems **202** also include one or more of a path calculator **214**, an object data calculator **216**, an object classifier **218**, a collision predictor system **220**, a kinematics calculator **222**, and a safety system actuator **224**. The vehicle systems **202** may be configured to access one or more data stores including, but not limited to, an object type data store **226**. The object type data store **226** may include data representing object types associated with object classifications for objects detected in the environment **100**.

The example vehicle systems **202** shown in FIG. **2** also include a vehicle controller **228** configured to receive vehicle control data **230**, and based on the vehicle control data **230**, communicate with a drive system **232** (e.g., a steering system, a propulsion system, suspension system, and/or a braking system) to control operation of the vehicle **102**. For example, the vehicle control data **230** may be derived from data received from one or more of the sensors **204** and one or more of the path calculator **214**, the object data calculator **216**, the object classifier **218**, the collision predictor system **220**, the kinematics calculator **222**, and the safety system actuator **224**, and control operation of the drive system **232**, so that operation and maneuvering of the vehicle **102** is executed.

In some examples, the path calculator **214** may comprise a software and/or hardware component of the vehicle controller **228**, and the path calculator **214** may be configured to generate data representative of a trajectory of the vehicle **102**, for example, using data representing a location of the vehicle **102** in the environment **100** and other data, such as local pose data, that may be included in the location data **212**. In some examples, the path calculator **214** may also be configured to determine projected trajectories predicted to be executed by the vehicle **102**. The path calculator **214** may, in some examples, be configured to calculate data associated with a predicted motion of an object in the environment **100**, and may determine a predicted object path associated with the predicted motion of the object. In some examples, the object path may include the predicted object path. In some examples, the object path may include a predicted object trajectory. In some examples, the path calculator **214** may be

configured to predict more than a single predicted object trajectory. For example, the path calculator **214** may be configured to predict multiple object trajectories based on, for example, probabilistic determinations or multi-modal distributions of predicted positions, trajectories, and/or velocities associated with an object. In any of the examples described herein, the path calculator **214** may be configured to generate and/or otherwise determine a path along or within which the vehicle **102** will travel, and such a path may be determined by the path calculator **214** based at least partly on and/or in accordance with a set of parameters provided by the remote vehicle control system **154**. In particular, in some examples the path calculator **214** may be configured to determine a drive envelope **138** defining and/or including a drive line **146** along or within which the vehicle **102** will travel to the destination **124**. Such a drive line **146** may indicate an ideal line for the vehicle **102** to follow and may further comprise one or more trajectories (e.g., a series of consecutive trajectories), and the drive line **146** and/or such trajectories may define a prioritized path extending from the vehicle **102** to the destination **124**.

In some examples, the object data calculator **216** may be configured to provide data representative of, for example, one or more of the location of an object in the environment **100** surrounding the vehicle **102**, an object track associated with the object, and an object classification associated with the object. For example, the object data calculator **216** may be configured to receive data in the form of sensor signals received from one or more of the sensors **204** and determine data representing one or more of the location in the environment **100** of the object, the object track, and the object classification.

In some examples, the object classifier **218** may be configured to access data from the object type data store **226**, which may be configured to store data representing object types, such as, for example, a species of an object classification, a subclass of an object classification, and/or a subset of an object classification. The object classifier **218**, in some examples, may be configured to analyze data representing an object track and data representing an object classification with data representing an object type, and determine an object type based at least in part on the object track and classification data. For example, a detected object having an object classification of an "automobile" may have an object type of "sedan," "coupe," "hatch-back," "sports utility vehicle," "pick-up truck," or "minivan." An object type may include additional subclasses or subsets. For example, a "sedan" that is parked may have an additional subclass designation of being "static" or "being dynamic" if moving.

In some examples, the collision predictor system **220** may be configured to use the data representing the object type, the data representing the trajectory of the object, and/or the data representing the trajectory of the vehicle **102**, to predict a collision between the vehicle **102** and the object.

In some examples, the kinematics calculator **222** may be configured to determine data representing one or more scalar and/or vector quantities associated with motion of objects in the environment **100**, including, but not limited to, velocity, speed, acceleration, deceleration, momentum, local pose, and/or force. Data from the kinematics calculator **222** may be used to compute other data, including, but not limited to, data representing an estimated time to impact between an object and the vehicle **102**, and data representing a distance between the object and the vehicle **102**. In some examples, the kinematics calculator **222** may be configured to predict a likelihood that other objects in the environment **100** (e.g., cars, motorcyclists, pedestrians, cyclists, and animals) are



moving in an alert or controlled state, versus an un-alert or uncontrolled state. For example, the kinematics calculator **222** may be configured estimate the probability that other objects are moving as though they are being controlled and/or are behaving in a predictable manner, or whether they are not being controlled and/or behaving in an unpredictable manner, for example, by observing motion of the object over time and relative to other objects in the environment **100**. For example, if the objects are moving erratically or without appearing to adjust to the presence or motion of other objects in the environment **100**, this may be an indication that the objects are either uncontrolled or moving in an unpredictable manner. This may be inferred based on sensor data received over time that may be used to estimate or predict a future location of the object relative to a current or future trajectory of the vehicle **102**.

In some examples, the safety system actuator **224** may be configured to activate one or more safety systems of the vehicle **102** when a collision is predicted by the collision predictor **220** and/or the occurrence of other safety related events, such as, for example, an emergency maneuver by the vehicle **102**, such as hard braking or a sharp acceleration. The safety system actuator **224** may be configured to activate an interior safety system (e.g., including seat belt pre-tensioners and/or air bags), an exterior safety system (e.g., including warning sounds and/or warning lights), the drive system **232** configured to execute an emergency maneuver to avoid a collision, and/or any combination thereof. For example, the drive system **232** may receive data for causing a steering system of the vehicle **102** to change the travel direction of the vehicle **102**, and a propulsion system of the vehicle **102** to change the speed of the vehicle **102** to alter the trajectory of vehicle **102** from an initial trajectory to a trajectory for avoiding a collision.

The vehicle systems **202** may operate according to the following example. Data representing a trajectory of the vehicle **102** in the environment **100** may be received by the vehicle controller **228**. Object data associated with an object in the environment **100** surrounding the vehicle **102** may be calculated. Sensor data **206** from one or more of the sensors **204** may be used to calculate the object data. The object data may include data representing the location of the object in the environment **100**, an object track associated with the object, such as whether the object is stationary or moving, and an object classification associated with the object, such as whether the object is another vehicle, a pedestrian, a cyclist, an animal, or a stationary object. In some examples, the object data calculator **216**, based on the object data, may be used to determine data representing the object's location in the environment **100**, data representing whether the object is moving, and data representing a classification associated with the object.

In some examples, the path calculator **214** may use the object data to determine a predicted path of the object in the environment, for example, based on data representing the location of the object and may process that data to generate data representing a predicted object path. Data representing the type of object may be determined based on the data representing whether the object is moving, data representing the object's classification, and/or data representing object's type. A pedestrian not in motion, a vehicle in motion, and traffic sign, a lane marker, or a fire hydrant, none of which is in motion, are examples of object types with an associated motion data.

In some examples, the collision predictor system **220** may be used to predict a collision between the vehicle **102** and an object in the environment **100** based on the object type,

whether the object is moving, the trajectory of the vehicle **102**, the predicted path of the object obtained from the path calculator **214**. For example, a collision may be predicted based in part on the object type due to the object moving, the trajectory of the object being in potential conflict with the trajectory of the vehicle **102**, and the object having an object classification that indicates the object is a likely collision threat.

In some examples, the safety system actuator **224** may be configured to actuate one or more portions of a safety system of the vehicle **102** when a collision is predicted. For example, the safety system actuator **224** may activate one or more safety systems of the vehicle **102**, such as, for example, one or more of the interior safety systems, one or more of the exterior safety systems, and one or more of the components of the drive system **232** (e.g., the steering system, the propulsion system, and/or the braking system) via the vehicle controller **228**. In some examples, the vehicle controller **228** may determine that the interior safety system will be activated based on some action of an object in the environment **100**, and the vehicle control data **230** may include information configured to cause the vehicle controller **228** to activate one or more functions of the interior safety system, the exterior safety system, and the drive system **232**.

As shown in FIG. 2, the example vehicle systems **202** also include a network interface **234** configured to provide a communication link between the vehicle **102** and the remote vehicle control system **154**. For example, the network interface **234** may be configured to allow data to be exchanged between the vehicle **102**, other devices coupled to the network **152**, such as other computer systems, other vehicles **102** in the fleet of vehicles, and/or with the remote vehicle control system **154**. For example, the network interface **234** may enable wireless communication between numerous vehicles and/or the remote vehicle control system **154**. In various implementations, the network interface **234** may support communication via a wireless general data networks, such as a Wi-Fi network. For example, the network interface **234** may support communication via telecommunications networks, such as, for example, cellular communication networks, satellite networks, and the like. Further, the vehicle controller **228** may provide, via the network interface **234**, signals corresponding to and/or containing information indicative of inputs received via the preferential travel input device **148**. The vehicle controller **228** may also provide information indicative of one or more travel paths (e.g., the prioritized described herein) and/or one or more additional parameters included in a set of parameters via the preferential travel output device **150**. Such information may be generated by the path calculator **214**. Additionally or alternatively, such information may be received, by the network interface **234**, from the remote vehicle control system **154** and via the network **152**. In some examples, the vehicle controller **228** may additionally, or alternatively, control a suspension system of the vehicle **102**. For example, in modifying operating parameters of the vehicle **102** based on a set of modified parameters received from the remote vehicle control system **154**, the vehicle controller **228** may lower a suspension of the vehicle **102**, increase a vehicle speed, stiffen a shock/strut response, and/or otherwise modify various vehicle component settings. As a result, the ride experience of a passenger may be altered. For example, controlling the vehicle **102** based on the received set of modified parameters may cause a passenger to experience enhanced accelerations in a lateral (e.g., sideways) direction, an axial direction (e.g., a direction substantially along the

drive line **146**), and/or a vertical direction (e.g., a direction substantially perpendicular to the road **106**).

In various implementations, the parameter values and other data illustrated herein may be included in one or more data stores, and may be combined with other information not described or may be partitioned differently into more, fewer, or different data structures. In some implementations, data stores may be physically located in one memory or may be distributed among two or more memories.

Those skilled in the art will appreciate that the example architecture **200** is merely illustrative and is not intended to limit the scope of the present disclosure. In particular, the computing system and devices may include any combination of hardware or software that can perform the indicated functions, including computers, network devices, internet appliances, tablet computers, PDAs, wireless phones, pagers, etc. The architecture **200** may also be connected to other devices that are not illustrated, or instead may operate as a stand-alone system. In addition, the functionality provided by the illustrated components may in some implementations be combined in fewer components or distributed in additional components. Similarly, in some implementations, the functionality of some of the illustrated components may not be provided and/or other additional functionality may be available.

Those skilled in the art will also appreciate that, while various items are illustrated as being stored in memory or storage while being used, these items or portions of them may be transferred between memory and other storage devices for purposes of memory management and data integrity. Alternatively, in other implementations, some or all of the software components may execute in memory on another device and communicate with the illustrated architecture **200**. Some or all of the system components or data structures may also be stored (e.g., as instructions or structured data) on a non-transitory, computer-accessible medium or a portable article to be read by an appropriate drive, various examples of which are described above. In some implementations, instructions stored on a computer-accessible medium separate from the architecture **200** may be transmitted to the architecture **200** via transmission media or signals such as electrical, electromagnetic, or digital signals, conveyed via a communication medium such as a wireless link. Various implementations may further include receiving, sending, or storing instructions and/or data implemented in accordance with the foregoing description on a computer-accessible medium. Accordingly, the techniques described herein may be practiced with other control system configurations.

FIG. **3** shows an example architecture **300** including a vehicle fleet **302** and an example remote vehicle control system **154**. The example vehicle fleet **302** includes a plurality of vehicles **102**, at least some which are communicatively coupled to the remote vehicle control system **154**, for example, via the respective network interfaces **234** of the vehicles **102**, and a receiver **304** and a transmitter **306** associated with the remote vehicle control system **154**. For example, a vehicle **102** may send communication signals via the network interface **234**, which are received by the receiver **304**. In some examples, the communication signals may include, for example, sensor data from sensor signals generated by one or more sensors associated with the vehicle **102**, and/or road network data from a road network data store. In some examples, the sensor data may include raw sensor data or processed sensor data, and the road network data may include data related to a global or local map of an area associated with operation of the vehicle **102**. In any of

the examples described herein, such road network data may also include one or more of lane widths, speed limits, or a road map. Such lane widths, speed limits, and road maps may correspond to the one or more roads **106** of the road network **104** described herein. In some examples, the communication signals may include data associated with the current status of the vehicle **102** and its systems, such as, for example, its current position, current speed, current path, current occupancy, the level of charge of one or more of its batteries, and/or the operational status of its sensors and drive systems. In some examples, the communication signals from the vehicle **102** may include a request for information from the remote vehicle control system **154**. Such information, may include, for example, assistance with operation of the vehicle **102** in the form of, for example, information about objects, the road network **104**, the road **106**, the global map, the local map, collaboration with respect to vehicle operations and maneuvers, and/or confirmation of information and/or actions proposed by the vehicle **102**. In some examples, the communication signals from the vehicle **102** may include a request for preferential travel associated with the vehicle **102** and a particular destination **124** accessible via the road network **104**. A passenger of the vehicle **102** may enter such a request via the preferential travel input device **148**, and such a request may include at least an address, coordinates, and/or other information indicating the location of the destination **124**.

As shown in FIG. **3**, the receiver **304** may be communicatively coupled to the computing device **160**, and in some examples, the operator **158** may be able access the sensor data, the road network data, and/or any other data in the communication signals received from a vehicle **102** using the computing device **160**. In some examples, the operator **158** may be able to selectively access the sensor data, road network data, and/or other data via the input device **164** and view the selected data via one or more of the displays **162** (see FIG. **1**). In some examples, such road network data may be stored in the object type data store **226** and/or in a road network data store operably connected to the vehicle controller **228**. Such a road network data store may comprise a component of the vehicle system **202**. In other examples, the road network data store may comprise a component of the remote vehicle control system **154** and may be operably connected to the computing device **160**. In still further examples, a first portion of the road network data store may comprise a component of the remote vehicle control system **154**, and a second portion of the road network data store may comprise a component of the vehicle system **202**.

In the example shown, the remote vehicle control system **154** also includes a network module **308** configured to provide communication between two or more of the computing device **160** and the respective operators **158**, and/or communication with vehicle control data **310**. For example, the remote vehicle control system **154** may include a plurality of computing devices **160** and respective operators **158**, and the operators **158** may communicate with one another via the network module **308** to facilitate and/or coordinate the various sets of parameters, path information, and/or other guidance provided to the vehicles **102** of the vehicle fleet **302**. In some examples, there may be an operator **158** assigned to each of the vehicles **102**, and in some examples, an operator **158** may be assigned to more than a single vehicle **102** of the vehicle fleet **302**. In some examples, operators **158** may not be assigned to specific vehicles **102** of the vehicle fleet **302**, but may instead provide sets of parameters, drive lines, trajectories, path information, and/or other guidance to vehicles **102** based on,

for example, a level of urgency and/or a level of priority associated with the respective vehicles 102. In some examples, the various sets of parameters, path information, and/or other guidance provided to the vehicles 102 of the vehicle fleet 302 by an operator 158 may be stored by the remote vehicle control system 154, for example, in storage for the vehicle control data 310, and/or accessed by other operators 158. Further, it is understood that in some examples, the remote vehicle control system 154 may be fully automated. In such examples, the operators 158 described herein may be omitted. Additionally, in other examples, any of the methods and/or functions described herein may be performed by one or more of the local vehicle controllers 228. In such examples, the remote vehicle control system 154 may be omitted.

In some examples, the vehicle control data 310 may be accessible by the operators 158, for example, via the computing device 160, for use in generating one or more sets of modified parameters, drive lines, trajectories, drive envelopes, path information, and/or other guidance to the vehicles 102. For example, the vehicle control data 310 may include global and/or local map data related to the road network 104, events associated with the road network 104, and/or travel conditions associated with the road network 104 due to, for example, traffic volume, weather conditions, construction zones, and/or special events. In some examples, the vehicle control data 310 may include data associated with one more of the vehicles 102 of the vehicle fleet 302, such as, for example, maintenance and service information, and/or operational history including, for example, event history associated with the vehicle 102, path histories, one or more sets of parameters governing operation of the vehicle 102, previously visited destinations 124, occupancy histories, and other types of data associated with the vehicle 102. In any of the examples described herein, and as noted above, one or more of the vehicles 102 may travel within a respective drive envelope 138 in accordance with a set of nominal operating parameters during normal operation. The one or more sets of modified operating parameters described herein may include, for example, an alteration (e.g., a relaxation or reduction) of at least one of the nominal operating parameters governing the current/normal operation of the vehicle 102. In another example, such a set of modified parameters may include at least one additional operating parameter not included in the nominal operating parameters. In a further example, such a set of modified parameters may omit one or more of the nominal operating parameters. In any such examples, upon receiving the set of modified parameters from the remote vehicle control system 154, the vehicle controller 228 may control operation of the vehicle 102 based at least in part on the set of modified operating parameters.

FIGS. 4a-7b illustrate example schematic overhead views of an example road network 104 including example vehicles 102a-102c (vehicles 102a-102f are shown in

FIGS. 6a and 6b, and collectively, the vehicles shown in FIGS. 4a-7b may be referred to herein as “vehicles 102”). In FIGS. 4a-7b, the vehicles 102 are shown en route between respective first geographic locations and respective destinations at second geographic areas. For example, FIG. 4a illustrates a first vehicle 102a traveling, in the first direction 132, in the first lane 110a of the road 106 toward a particular destination 124. One or more of the additional vehicles 102b, 102c may also be traveling en route to the destination 124, or alternatively, one or more of the vehicles 102b, 102c may be traveling to a different respective destination (not shown). In such examples, one or more of the vehicles 102

may travel within respective drive envelopes between respective first geographic locations 120 and respective destinations 124. It is understood that such drive envelopes may each present unique driving circumstances for the respective vehicles 102. For example, such drive envelopes may cause the respective vehicles to pass through or proximate an accident zone, a lane closure, merging traffic, a school zone, a crosswalk, a police officer directing traffic, a construction zone, or other areas requiring modifications to the speed, and/or other operations of the vehicles 102. Additionally, in some situations, one or more of the vehicles 102 may receive an input from one or more passengers of the vehicle 102 indicative of a request for preferential travel. In any of the above situations, the methods, systems, and/or other aspects of the present disclosure may be used to determine one or more sets of modified parameters governing operation of the respective vehicles 102 once preferential travel has been requested. An example set of modified parameters may be different from the set of nominal operating parameters currently governing operation of the vehicle 102, and may cause and/or require a requesting vehicle 102 to travel along a prioritized path to the destination 124 without being slowed or otherwise hindered by the remaining vehicles 102 in the road network 104. In particular, example command signals including respective sets of modified parameters may be provided to the vehicles 102. Upon receiving such sets of modified parameters, the vehicle controllers 228 of the respective vehicles 102 may cause and/or require the vehicles 102 to travel within respective drive envelopes such that the requesting vehicle 102 is provided with a free lane (e.g., the first lane 110a) or other portion of the road network 104 in order to reach the destination 124 expeditiously. In such examples, the vehicle controller 228 of each of the respective vehicles 102 may consume respective sets of modified parameters and/or other information included in such command signals, and the path calculator 214 of each of the respective vehicles may determine one or more trajectories, a drive line including each of the one or more trajectories, drive envelope including the drive line, and/or other items based at least partly on such command signals and/or sets of parameters. In some examples, such commands to the vehicle controller 228 may additionally, or alternatively, comprise an increase in speed with an accompanying change in vehicle suspension to provide passengers with a racecar-like experience. In some examples, such a request may be made by a first responder (e.g. ambulance, fire truck, police, etc.) to create a free lane for optimizing travel time of the first responders.

FIG. 4a illustrates an example embodiment in which the vehicle 102a is traveling along the road 106, in the first direction 132, toward a particular destination 124. In such examples, a passenger of the vehicle 102a may provide an input via the preferential travel input device 148 of the vehicle 102a. For example, the passenger may provide such an input by actuating, pressing, moving, touching, and/or otherwise contacting the preferential travel input device 148. Additionally or alternatively, the passenger may provide an input by speaking, waiving, making one or more hand gestures, and/or through other non-contact methods. Any such inputs may be indicative of a request for preferential travel between a current location of the vehicle 102a and the destination 124. As noted above, such a request may comprise a request for a prioritized path in which none of the additional vehicles in the road network are disposed within or along a drive envelop and/or trajectory of the requesting vehicle 102 as the requesting vehicle 102 travels to the particular destination 124. In such examples, the vehicle

**102a** may be controlled to travel along a trajectory for a finite period of time or for a finite distance. For example, such a drive envelope and/or trajectory may comprise a drive segment, line, and/or route along which the requesting vehicle **102a** may be controlled to travel for approximately 10 seconds. Alternatively, such a drive envelope and/or trajectory may comprise a drive segment, line, and/or route along which the requesting vehicle **102a** may be controlled to travel for the next 500 feet. It is understood that the finite period of time and finite distance noted above are merely examples and, in further embodiments, such finite periods of time and finite distances may be greater than or less than those noted above. For instance, in examples in which the requesting vehicle **102a** is traveling at a relatively high rate of speed, the finite period of time may be decreased and/or the finite distance may be commensurately increased to account for such speeds. Likewise, in examples in which the requesting vehicle **102a** is traveling at a relatively low rate of speed, the finite period of time may be increased and/or the finite distance may be commensurately decreased. In such examples, it may be permissible for such additional vehicles **102b**, **102c** to be traveling in one or more lanes **110** (e.g., the first lane **110a**) adjacent to the second lane **110b** in which the requesting vehicle **102a** is traveling, as such locations would be outside of the trajectory of the requesting vehicle **102a**.

The vehicle controller **228** in communication with the preferential travel input device **148** may generate a signal indicative of the request for preferential travel, and the vehicle controller **228** may provide the signal to the remote vehicle control system **154**, via the network **152**. The remote vehicle control system **154** may determine respective sets of modified parameters for the one or more vehicles **102** in the road network **104** based at least partly on the request. In some examples, the sets of modified parameters may include respective drive envelopes, trajectories, drive lines, drive envelopes and/or parameters governing travel of the respective vehicles **102** in the road network **104**. Alternatively, the sets of parameters may provide information and or instructions which, when consumed by a vehicle controller **228** may cause the path calculator **214** to generate and/or otherwise determine one or more trajectories, a drive line, a drive envelope, and/or other parameters governing travel of the corresponding vehicle. The remote vehicle control system **154** may also provide corresponding command signals to the respective vehicles **102**, and the command signals may each include one or more of the respective sets of parameters described herein. In some examples, a set of parameters included in a command signal received by the requesting vehicle **102a** may cause the vehicle **102a** to move from the first lane **110a** to the second lane **110b** in the direction of arrow **400**. In such examples, as will be described below, one or more drive envelopes defining a prioritized path to the destination **124** may be at least partly defined by and/or may pass substantially along the second lane **110b**. Additionally, the set of parameters included in the command signal received by the requesting vehicle **102a** may cause the vehicle **102a** to accelerate and/or decelerate in order to move in the direction of arrow **400** and/or to travel along such drive line. Such sets of parameters may also cause modification of a suspension setting, speed threshold, engine setting, turbo setting, brake setting, and/or other operating parameter of a respective vehicle **102**. As a non-limiting example, the suspension may be lowered during the initial acceleration into the prioritized trajectory and/or along the drive line defined by arrow **400** such that the passenger requesting the prioritization experiences modified vehicle

settings that correspond to the prioritization request and/or to preference of the passenger.

FIG. **4b** illustrates the example of FIG. **4a** after the vehicles **102a**, **102b**, **102c** have been caused to operate in accordance with the command signals described above. For example, upon receiving a first command signal from the remote vehicle control system **154** including a first set of parameters, the first vehicle **102a** may be caused to travel along a prioritized path **402** (e.g., a first path **402** extending from the vehicle **102a** to the destination **124**). The first path **402** may comprise the drive line **146** and/or a first drive envelope **138** that includes the drive line **146**, i.e. an ideal line for the vehicle **102** to follow. For example, the first path **402** may comprise a series of consecutive prioritized trajectories, and together, such trajectories may define the drive line **146** within the drive envelope **138**. In such examples, the vehicle **102a** may travel along the drive line **146**, and the drive line **146** may extend approximately centrally through the drive envelope **138** and/or the first path **402**. Additionally, upon receiving respective second and third command signals from the remote vehicle control system **154** including respective second and third sets of parameters, the second vehicle **102b** and the third vehicle **102c** may be caused to travel along respective drive lines maintaining the vehicles **102b**, **102c** outside of the drive envelopes and/or one or more trajectories defining the drive line **146** of the requesting vehicle **102a** as the requesting vehicle **102a** travels to the particular destination **124** along the prioritized path **402**. In particular, upon receiving a second command signal from the remote vehicle control system **154**, the second vehicle **102b** may be caused to travel within a second drive envelope **406** defined by and/or including a corresponding third drive line (not shown), and upon receiving a third command signal from the remote vehicle control system **154**, the third vehicle **102c** may be caused to travel within a third drive envelope **408** defined by and/or including a corresponding third drive line (not shown). Based on the sets of modified parameters included in such second and third control signals, the respective vehicle controllers **228** of the second and third vehicles **102b**, **102c** may maintain the second and third vehicles **102b**, **102c** outside of the drive envelope(s) and/or one or more trajectories defining the drive line **146** of the requesting vehicle **102a** as the requesting vehicle **102a** travels to the particular destination **124** along the prioritized path **402**. The sets of parameters included in the command signals received by the second and third vehicles **102b**, **102c** may also cause at least one of the second and third vehicles **102b**, **102c** to accelerate and/or decelerate in order to travel within the second and third drive envelopes **406**, **408**, respectively.

Additionally, in such examples the first set of parameters may be at least partly less restrictive than the second and third sets of parameters, thereby providing the first vehicle **102a** with expanded road network usage privileges relative to the remaining vehicles **102** in the road network **104**. For instance, in any of the examples described herein, the sets of parameters may include a speed threshold below which a respective one of the vehicles **102** may be permitted and, in some situations, required to operate, a drive line **146** along which the one of the vehicles **102** may be permitted and, in some situations, required to travel, a drive envelope **138** and/or path along which or within which the one of the vehicles **102** may be permitted and, in some situations, required to travel, traffic rules (e.g., rules governing vehicle operation with regard to stop signs, traffic lights, no passing zones, school zones, or other areas) with which the one of the vehicles **102** must abide, engine, turbo, brake, suspen-

sion, and/or other vehicle component settings, and/or other rules or limitations for operating the one of the vehicles 102. In such examples, the thresholds, drive envelopes, traffic rules, vehicle component settings, and/or other rules or limitations included in the first set of parameters may be at least partly less restrictive than the corresponding rules or limitations included in the additional sets of parameters determined by the remote vehicle control system 154.

Although FIGS. 4a and 4b illustrate an example embodiment in which the requesting vehicle 102a may be caused to move from a first lane 110a to a second lane 110b, in other examples various command signals provided by the remote vehicle control system 154 may include respective sets of modified parameters that cause vehicles 102 other than the requesting vehicle 102a to change lanes. For example, FIGS. 5a and 5b illustrate an example embodiment in which the requesting vehicle 102a may be controlled to remain in the first lane 110a (e.g., the lane in which the requesting vehicle 102a is currently traveling) and in which one or more of the additional vehicles 102 traveling along the road 106 may be caused to move from the lane in which the requesting vehicle 102a is currently traveling (e.g., the first lane 110a) to the second lane 110b and/or any other lane different from the lane in which the requesting vehicle 102a is currently traveling. In such examples, and as illustrated in FIG. 5a, the vehicle 102a may be traveling in the first direction 132 toward a particular destination 124. During such travel, a passenger of the vehicle 102a may provide an input via the preferential travel input device 148 of the vehicle 102a, and the input may be indicative of a request for prioritized travel between a current location of the vehicle 102a and the destination 124.

The vehicle controller 228 in communication with the preferential travel input device 148 of the requesting vehicle 102a may generate a signal indicative of the request for preferential travel, and the vehicle controller 228 may provide the signal to the remote vehicle control system 154, via the network 152. The remote vehicle control system 154 may determine respective sets of modified parameters for the one or more vehicles 102 in the road network 104 based at least partly on the request. In some examples, the sets of modified parameters may include respective trajectories, drive lines, drive envelopes, and/or other parameters governing travel of the respective vehicles 102 in the road network 104. Alternatively, the sets of parameters may provide information and/or instructions which, when consumed by a vehicle controller 228 may cause the path calculator 214 to generate and/or otherwise determine one or more trajectories, a drive line, a drive envelope, and/or other parameters governing travel of the corresponding vehicle. Such respective sets of parameters may also include any of the additional settings, thresholds, rules, limitations, or other parameters described herein. The remote vehicle control system 154 may also provide corresponding command signals to the respective vehicles 102, and the command signals may each include one or more of the respective sets of parameters described herein.

In the embodiment illustrated by FIG. 5a, a command signal received by the requesting vehicle 102a and including a first set of parameters may cause the vehicle 102a to remain in its current lane (i.e., first lane 110a). In such examples, a prioritized path extending from the requesting vehicle 102a to the destination 124 may be at least partly defined by and/or may pass substantially along the first lane 110a. Additionally, the command signals received by the remaining vehicles 102b, 102c in the road network 104 and including respective second and third sets of parameters,

may cause one or more of the vehicles 102b, 102c to move in the direction of arrow 500 from the first lane 110a to the second lane 110b and/or any other lane different from the first lane 110a. In any such examples, one or more sets of parameters included in the command signals may cause a respective vehicle 102 to accelerate and/or decelerate in order to change from the first lane 110a to the second lane 110b, and/or to travel along a respective trajectory. Such sets of parameters may also cause modification of a suspension setting, speed threshold, engine setting, turbo setting, brake setting, and/or other operating parameter of a respective vehicle 102, as described herein.

FIG. 5b illustrates the embodiment of FIG. 5a after the vehicles 102a, 102b, 102c have been caused to operate in accordance with the command signals described above. For example, upon receiving a first command signal from the remote vehicle control system 154 including a first set of parameters, the first vehicle 102a may be caused to travel along a prioritized path 502 (e.g., a first path 502 extending from the vehicle 102a to the destination 124). The first path 502 may comprise the drive line 146 and/or a first drive envelope 138 that includes and/or is defined by the drive line 146. In such examples, the vehicle 102a may travel along the drive line 146, and the drive line 146 may extend approximately centrally through the drive envelope 138 and/or the first path 502. As illustrated in FIG. 5b, the first drive envelope 138 and the respective drive line 146 may be substantially longer than those of vehicles 102b, 102c (i.e. 506 and 508) despite corresponding to a substantially similar receding horizon (e.g. 10 seconds). In such an example, the longer drive envelope 138/drive line 146 of vehicle 102a may be indicative of a greater rate of travel (i.e. speed) than either vehicle 102b, 102c. In the example shown in FIG. 5b, the command signal received from the remote vehicle control system 154 may cause the vehicle 102a to remain in the first lane 110a as the vehicle 102a travels along at least part of the first path 502.

Additionally, upon receiving respective second and third command signals from the remote vehicle control system 154 including respective second and third sets of parameters, the second vehicle 102b and the third vehicle 102c may be caused to travel along respective drive lines maintaining the vehicles 102b, 102c outside of the one or more drive envelopes and/or trajectories defining the drive line 146 of the requesting vehicle 102a as the requesting vehicle 102a travels to the destination 124 along the prioritized path 502. In particular, upon receiving a second command signal from the remote vehicle control system 154, the second vehicle 102b may be caused to travel within a second drive envelope 506 defined by and/or including a corresponding second drive line (not show), and upon receiving a third command signal from the remote vehicle control system 154, the third vehicle 102c may be caused to travel within a third drive envelope 508 defined by and/or including a corresponding third drive line (not show). Based on the sets of modified parameters included in such second and third control signals, the respective vehicle controllers 228 of the second and third vehicles 102b, 102c may maintain the second and third vehicles 102b, 102c outside of the one or more drive envelopes and/or trajectories defining the drive line 146 of the requesting vehicle 102a as the requesting vehicle 102a travels to the destination 124 along the prioritized path 502. The sets of parameters included in the respective command signals received by the second and third vehicles 102b, 102c may cause at least one of the second and third vehicles 102b, 102c to accelerate and/or decelerate in order to travel within the second and third drive

envelopes **506**, **508**, respectively. For example, the set of parameters included in the command signal received by the second vehicle **102b** may cause the vehicle **102b** to accelerate in order to move in the direction of arrow **500** and/or to change from the first lane **110a** to the second lane **110b**. Additionally or alternatively, the set of parameters included in the command signal received by the third vehicle **102c** may cause the third vehicle **102c** to decelerate in order to permit the second vehicle **102b** to pass in front of the third vehicle **102c**. Additionally, in such examples the first set of parameters may be at least partly less restrictive than the second and third sets of parameters, thereby providing the first vehicle **102a** with expanded road network usage privileges relative to the remaining vehicles **102** in the road network **104**.

In any of the examples described herein, the sets of parameters determined and/or provided by the remote vehicle control system **154** at least partly in response to a request for preferential travel may be determined such that a minimum number of vehicles **102** are caused to change lanes **110** when preferential travel is provided to the requesting vehicle **102a**. Such determinations may be made based on the relative speeds, destinations, applicable traffic rules, and/or locations of the plurality of vehicles **102** in the road network **104** when the request for preferential travel is received by the remote vehicle control system **154**. For example, relatively congested traffic patterns proximate the requesting vehicle **102a** may cause the remote vehicle control system **154** to determine one or more sets of modified parameters that result in the requesting vehicle **102a** and at least one of the remaining vehicles **102** in the road network **104** to change lanes. FIGS. **6a** and **6b** illustrate such an example in the context of a road **106** having three lanes **110** (e.g., a first lane **110a**, a second lane **110b**, and a third lane **110c**) separated by respective dividing lines **114a**, **114b**.

As shown in FIG. **6a**, a first vehicle **102a** may be traveling in the first direction **132** toward a particular destination **124**. During such travel, a passenger of the vehicle **102a** may provide an input via the preferential travel input device **148** of the vehicle **102a**, and the input may be indicative of a request for preferential travel from a current location of the vehicle **102a** to the destination **124**. The vehicle controller **228** in communication with the preferential travel input device **148** of the requesting vehicle **102a** may generate a signal indicative of the request for preferential travel, and the vehicle controller **228** may provide the signal to the remote vehicle control system **154**, via the network **152**. The remote vehicle control system **154** may determine respective sets of modified parameters for the one or more vehicles **102** in the road network **104** based at least partly on the request. The remote vehicle control system **154** may also provide corresponding command signals to the respective vehicles **102**, and the command signals may each include respective sets of modified parameters as described herein.

In the embodiment illustrated by FIG. **6a**, a first set of modified parameters included in a command signal received by the requesting vehicle **102a** may cause the vehicle **102a** to move, in the direction of arrow **600**, from its current lane (e.g., the third lane **110c**) to an adjacent lane (e.g., the second lane **110b**). Such movement may be the result of relatively congested traffic ahead of the vehicle **102a** in the third lane **110c** and/or by relatively less congested traffic ahead of the vehicle **102a** in the second lane **110b** and/or any other adjacent lane. For example, the presence of vehicles **102f**, **102e** ahead of the vehicle **102a** in the third lane **110c**, as well as the positions of the vehicles **102f**, **102e** relative to the vehicle **102b**, and the position of vehicle **102b** relative to

vehicles **102c**, **102d**, may cause the remote vehicle control system **154** to generate a first set of modified parameters. When such a first set of parameters is consumed by the vehicle controller **228** of the requesting vehicle **102a**, the first set of parameters may cause the path calculator **214** to generate a prioritized path, extending from the requesting vehicle **102a** to the destination **124**, and resulting in the requesting vehicle **102a** moving from the third lane **110c** to the second lane **110b**. The remote vehicle control system **154** may also determine additional sets of parameters for one or more of the vehicles **102** based at least in part on the travel speeds of the vehicles **102** when the request from the vehicle **102a** is received. For example, since the requesting vehicle **102a** is positioned behind vehicles **102f**, **102e**, movement of the vehicle **102a** in the direction of arrow **600**, combined with movement of the vehicle **102b** in the direction or arrow **602**, may result in the most expedient development of a lane (e.g., the second lane **110b**) in which the requesting vehicle **102a** may have a relatively clear path to the destination **124**, particularly in situations in which for example, the nominal operating parameters of at least one of the vehicles **102e**, **102f** cannot be modified. For example, since the vehicle **102b** is currently the only vehicle in the second lane **110b**, and the vehicle **102b** is relatively behind vehicle **102e** but relatively ahead of vehicle **102c** in the direction **132**, the remote vehicle control system **154** and/or the path calculator **214** of at least the requesting vehicle **102a** may determine that movement of the vehicle **102a** in the direction of arrow **600**, combined with movement of the vehicle **102b** in the direction or arrow **602**, may be the most efficient manner in which to provide a prioritized path for the vehicle **102a** to the destination **124**. In such examples, maximizing efficiency may result in the fewest number of vehicles **102** changing lanes **110**, and may depend on, for example, the nominal operating parameters of the various vehicles **102** and whether such parameters may be modified. Additionally or alternatively, maximizing efficiency may result in the fastest travel path for the requesting vehicle **102a** to the destination **124** (e.g., a prioritized path in which the fewest number of vehicles **102** are required to decelerate, the path in which the speed of the requesting vehicle **102a** may be maximized, and/or the path in which the travel time for the requesting vehicle **102a** from its current location to the destination **124** may be minimized). In any such examples, a set of parameters included in one or more of the command signals may cause a respective one of the vehicles **102** to accelerate and/or decelerate in order to move between lanes **110** and/or to travel along respective drive lines.

FIG. **6b** illustrates the embodiment of FIG. **6a** after the vehicles **102a-102f** have been caused to operate in accordance with the command signals described above. For example, upon receiving a first command signal from the remote vehicle control system **154** including a first set of parameters, the first vehicle **102a** may be caused to travel along a prioritized path **604** (e.g., a first path **604** extending from the vehicle **102a** to the destination **124**). The first path **604** may comprise the drive line **146** and/or a first drive envelope **138** that includes the drive line **146**. For example, the first path **604** may comprise a series of consecutive prioritized trajectories, and together, such trajectories may define the drive line **146** within the drive envelope **138**. In such examples, the requesting vehicle **102a** may travel along the drive line **146**, and the drive line **146** may extend approximately centrally through the drive envelope **138** and/or the first path **604**. In the example shown in FIG. **6b**, the set of parameters included in the command signal received from the remote vehicle control system **154** may

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cause the vehicle **102a** to move from the third lane **110c** to the second lane **110b**. In such examples, additional sets of parameters included in respective command signals received by the remaining vehicles **102** in the road network **104** may cause the remaining vehicles **102** to travel along respective drive lines maintaining the remaining vehicles **102** outside of the one or more drive envelopes and/or trajectories defining the drive line **146** as the requesting vehicle **102a** travels to the particular destination **124** along the prioritized path **604**.

For example, upon receiving a command signal from the remote vehicle control system **154** including a second set of parameters, the second vehicle **102b** may be caused to travel within a second drive envelope **608** defined by and/or including a corresponding second drive line (not shown). In the example shown in FIG. **6b**, the second set of parameters included in the command signal received from the remote vehicle control system **154** may cause the vehicle **102b** to move from the second lane **110b** to the first lane **110a**. Further, additional sets of parameters included in respective command signals from the remote vehicle control system **154** may cause the remaining vehicles **102** to travel within respective drive envelopes maintaining the remaining vehicles **102** outside of the one or more drive envelopes and/or trajectories defining the drive line **146** as the requesting vehicle **102a** travels to the particular destination **124** along the prioritized path **604**. In particular, upon receiving a third command signal from the remote vehicle control system **154** including a third set of parameters, the third vehicle **102c** may be caused to travel within a third drive envelope **610** defined by and/or including a corresponding third drive line (not shown). The sets of parameters included in respective command signals received by the additional vehicles **102** in the road network **104** may also be consumed by the vehicle controllers **228** of such vehicles **102**, and may maintain such remaining vehicles **102** outside of the one or more trajectories defining the drive line **146** as the requesting vehicle **102a** travels to the particular destination **124** along the prioritized path **604**. The sets of parameters included in the respective command signals received by the remaining vehicles **102** may also cause at least one of the remaining vehicles **102** to accelerate and/or decelerate in order to travel within the respective drive envelopes described herein. For example, the set of parameters included in the command signal received by the second vehicle **102b** may cause the second vehicle **102b** to accelerate in order to move in the direction of arrow **602** and/or to change from the second lane **110b** to the first lane **110a**. Additionally or alternatively, the set of parameters included in the command signal received by the third vehicle **102c** may cause the third vehicle **102c** to decelerate in order to permit the second vehicle **102b** to pass in front of the third vehicle **102c**. In such examples, the first set of parameters may be at least partially less restrictive than the second and third sets of parameters, thereby providing expanded road network usage privileges to the requesting vehicle **102a**.

Although FIGS. **4a-6b** illustrate example embodiments in which typical traffic rules (e.g., rules governing vehicle operation with regard to stop signs, traffic lights, no passing zones, school zones, construction zones, lane designations, speed limits, etc.) are substantially obeyed by the vehicles **102** in the road network **104** once a request for preferential travel is received. In additional embodiments, on the other hand, providing a requesting vehicle **102a** with preferential travel may include permitting the requesting vehicle **102a** to at least temporarily break one or more traffic rules in order to travel along a prioritized path to the particular destination

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**124**. For example, FIGS. **7a** and **7b** illustrate an embodiment in which the requesting vehicle **102a** may be controlled to travel along a prioritized path that is at least partly defined by a drive envelope having an enlarged drive envelope width relative to drive envelope widths corresponding to the remaining vehicles **102** in the road network. In such examples, the drive envelope of the requesting vehicle **102a** may also straddle at least two lanes **110a**, **110b** of the road **106**. Further, in traveling to the destination **124**, the requesting vehicle **102a** may be permitted to exceed an applicable speed limit associated with the road **106**, may be permitted to ignore double yellow lines, may be permitted to travel abnormally close to an adjacent vehicle (e.g., travel at a distance of one foot or less from an adjacent vehicle), and/or may be configured to modify (e.g., enhance) vision, perception, or other systems of the vehicle **102**.

As illustrated in FIG. **7a**, the first vehicle **102a** may be traveling in the first direction **132** toward a particular destination **124**. The first vehicle **102a** may be traveling, for example, along a first path **702** extending from the first vehicle **102a** to the destination. In such examples, the first path **702** may be at least partly defined by a first drive envelope **138a** having a first drive envelope width **142a**. Additionally, the road network **104** may include a second vehicle **102b** traveling along a second path **704** that is at least partly defined by a second drive envelope **138b** having a second drive envelope width **142b**. The road network **104** may further include a third vehicle **102c** traveling along a third path **706** that is at least partly defined by a third drive envelope **138c** having a third drive envelope width **142c**. In the example embodiment of FIG. **7a**, the first, second, and third drive envelope widths **142a**, **142b**, **142c** may be substantially equal. Additionally, at least one of the first, second, and third drive envelope widths **142a**, **142b**, **142c** may be less than or equal to a width of a corresponding lane **110a**, **110b** within which the respective drive envelope **138a**, **138b**, **138c** is disposed. In such examples, the first drive envelope **138a**, the second drive envelope **138b**, and the third drive envelope **138c** may each be disposed within either the first lane **110a** or the second lane **110b**.

In such examples, a passenger of the first vehicle **102a** may provide an input via the preferential travel input device **148** of the first vehicle **102a**, and the input may be indicative of a request for preferential travel between a current location of the first vehicle **102a** and the destination **124**. The vehicle controller **228** in communication with the preferential travel input device **148** of the first vehicle **102a** may generate a signal indicative of the request for preferential travel, and the vehicle controller **228** may provide the signal to the remote vehicle control system **154** via the network **152**. The remote vehicle control system **154** may determine respective sets of modified parameters for the one or more vehicles **102** in the road network **104** based at least partly on the request. The remote vehicle control system **154** may also provide corresponding command signals to the respective vehicles **102**, and the command signals may each include one or more of the respective sets of modified parameters described herein.

In the embodiment illustrated by FIG. **7b**, a command signal received by the requesting vehicle **102a** and including a first set of modified parameters may cause the requesting vehicle **102a** to travel along a prioritized path **708** extending from the vehicle **102a** to the destination **124**. In such examples, the prioritized path **708** may include a respective drive line comprising one or more consecutive prioritized trajectories (not shown), and may be defined, at least in part, by a fourth drive envelope **138d** having a fourth drive

envelope width **142d** greater than the first drive envelope width **142a**. As shown in FIG. **7b**, the fourth drive envelope **138d** and/or the prioritized path **708** may span at least part of both the first lane **110a** and the second lane **110b**. The requesting vehicle **102a** may be permitted to travel within such a widened prioritized path **708** and/or fourth drive envelope **138d** despite applicable traffic rules requiring vehicles **102** to travel in a single lane **110a**, **110b** unless passing another vehicle **102**.

In such examples, the command signal received by the requesting vehicle **102a** and including such a first set of parameters may also cause the requesting vehicle **102a** to travel at a speed less than or equal to an increased speed threshold. In such examples, the increased speed threshold may be included in the command signal and may, in some instances, be greater than the speed limit associated with the road **106**. In such examples, the command signal received by the requesting vehicle **102a** and including such a first set of parameters may further include a modified suspension setting, engine setting, brake pressure setting, turbo setting, and/or other operational parameter. Such modified settings may cause the requesting vehicle **102a** to operate based at least in part on settings and/or operating preferences corresponding to the request and/or corresponding to the personal preferences of one or more passengers of the requesting vehicle **102a**.

Additionally, the command signals received by the remaining vehicles **102b**, **102c** in the road network **104** and including respective second and third sets of parameters, may cause one or more of the vehicles **102b**, **102c** to move closer to the lane boundary lines **116a**, **116b** and/or shoulders corresponding to the lanes **110a**, **110b** within which the vehicles **102b**, **102c** are traveling. The command signals received by the remaining vehicles **102b**, **102c** in the road network **104** and including respective second and third sets of parameters, may also cause one or more of the vehicles **102b**, **102c** to travel within respective drive envelopes having reduced width. For example, a second set of parameters included in the command signal received by the second vehicle **102b** may cause the second vehicle **102b** to travel in a fifth path **710** that is defined, at least in part, by a fifth drive envelope **138e** having a fifth drive envelope width **142e** less than the second drive envelope width **142b**. Additionally, a third set of parameters included in the command signal received by the third vehicle **102c** may cause the third vehicle **102c** to travel in a sixth path **712** that is defined, at least in part, by a sixth drive envelope **138f** having a sixth drive envelope width **142f** less than the third drive envelope width **142c**. As shown in FIG. **7b**, the fifth and sixth drive envelopes **138e**, **138f** may span only a portion of the respective lane **110a**, **110b** within which the second and third vehicles **102b**, **102c** are traveling. Further, the fifth and sixth drive envelope widths **142e**, **142f** may be less than the fourth drive envelope width **142d**. In this way, the requesting vehicle **102a** may be granted enhanced road network usage privileges at least partly in response to a request for preferential travel.

In some examples, the vehicles **102** illustrated in FIGS. **4a-7b** may be driverless non-emergency passenger vehicles. In other examples, on the other hand, at least the requesting vehicle **102a** illustrated in FIGS. **4a-7b** may comprise emergency response vehicles (e.g., ambulances, fire trucks, police cars, military vehicles, etc.), whether driverless or not. In any such example described herein, additional command signals may be sent to one or more traffic lights or other traffic control devices along the prioritized path. For example, such additional command signals may change all

traffic lights to “green” along the prioritized path such that the requesting vehicle **102a** may not have to stop at “red” traffic lights in emergency situations. Such situations may include, for example, situations in which a health emergency (e.g., a stroke, a heart attack, etc.) occurs within the requesting vehicle **102a**. In still further examples, any of the systems or methods described herein may also be employed by standard (e.g., non-driverless) vehicles. For example, a standard ambulance, fire truck, police car, or other non-driverless emergency vehicle, or a control system associated therewith, may provide a signal to one or more of the vehicles **102** that an emergency situation has occurred. In response, one or more of the vehicles **102** may be controlled to clear a path (e.g., a prioritized path) for one or more non-driverless emergency vehicles. In any of the examples described herein, one or more of the vehicles **102** may mimic an ambulance, fire truck, police car, or other emergency response vehicle in one or more ways. For example, upon receiving a command signal from the remote vehicle control system **154**, the vehicle controller **228** of the requesting vehicle **102** may cause one or more lights, sirens, horns, and/or other output components of the vehicle **102** to activate. In such examples, one or more lights, light bars, or other visual output devices of the vehicle **102** may be caused to flash as the vehicle **102** is controlled to traverse a prioritized path in the road network **104**. Additionally or alternatively, in such examples, one or more horns, sirens, speakers, or other audio output devices of the vehicle **102** may be caused to emit an audible tone as the vehicle **102** is controlled to traverse a prioritized path. In this way, such output may cause and/or enable other vehicles **102** in the road network **104** to move from or exit the drive envelope of the requesting vehicle **102** emitting such output without the other vehicles receiving a command signal causing such movement.

As noted above, in any of the examples described herein the sets of parameters included in the various command signals provided by the remote vehicle control system **154** may include instructions that cause the vehicle controllers **228** of the respective vehicles **102** to modify one or more performance parameters of the respective vehicles **102** (e.g., speed, acceleration, suspension settings, brake pressure settings, braking rates, engine settings, turbo settings, steering input rates, etc.) and/or operation parameters of the respective vehicles **102** (e.g., safety-related guidelines for controlling the vehicle). Additionally, although not specifically illustrated in FIGS. **4a-7b**, one or more conditions or events associated with the road network **104** may modify the travel paths, trajectories, drive lines, drive envelopes, and/or other parameters described herein. Such conditions or events may include accidents, school, and construction zones, flood zones, parade zones, special event zones, and/or zones associated with slow traffic, such as areas where vehicles are being driven into bright sunlight or areas where weather conditions such as rain or snow are affecting traffic rates.

FIG. **8** is a flow diagram of an example process illustrated as a collection of blocks in a logical flow graph. The various blocks shown in FIG. **8** represent a sequence of operations that can be implemented in hardware, software, or a combination thereof. In the context of software, the blocks represent computer-executable instructions stored on one or more computer-readable storage media that, when executed by one or more processors, perform the recited operations. Generally, computer-executable instructions include routines, programs, objects, components, data structures, and the like that perform particular functions or implement particular abstract data types. The order in which the opera-



tions are described is not intended to be construed as a limitation, and any number of the described blocks can be combined in any order and/or in parallel to implement the processes.

In particular, FIG. 8 is a flow diagram of an example method 800 for operating one or more vehicles (e.g., one or more driverless vehicles). At 802, the example method 800 may include receiving, at the computing device 160 and/or other components of the remote vehicle control system 154, sensor signals including sensor data 206 from one or more sensors 204 associated with a plurality of vehicles 102 (e.g., a plurality of driverless vehicles). In some examples, the sensor data 206 may be related to operation of the respective vehicles 102 to which the sensors 204 are connected. For example, the sensor data 206 may include sensor signals associated with the environment 100 through which the vehicles 102 are traveling. In some examples, the sensor data 206 may include sensor signals indicative of a respective location, speed, and/or other operational parameter of each vehicle 102 traversing the road network 104. It is understood that each vehicle 102 may have one or more sensors 204 connected thereto, and in such examples, the sensor signals received at 802 may comprise respective signals generated by the sensors 204 connected to the various individual vehicles 102 in the road network 104. Further, each vehicle 102 of the plurality of vehicles may have a number, alpha-numeric code, and/or other identifier assigned thereto and uniquely identifying the vehicle 102. In such examples, the sensor signals received at 802 may also include the unique identifier corresponding to the vehicle 102 to which the one or more sensors 204 generating the signal is/are connected.

At 804, the example method 800 may include receiving, at the computing device 160 and/or other components of the remote vehicle control system 154, a request from one or more of the vehicles 102, and such a request may comprise a request for preferential travel from a current location of the requesting vehicle 102 to a particular destination 124. For example, while traversing the road 106, a passenger of a first vehicle 102a may provide an input via the preferential travel input device 148 of the vehicle 102a. For example, the passenger may provide such an input by actuating, pressing, moving, touching, and/or otherwise contacting the preferential travel input device 148. Additionally or alternatively, the passenger may provide an input by speaking, waiving, making one or more hand gestures, and/or through other non-contact methods. Any such inputs may be indicative of a request for preferential travel within the road network 104 between the current location of the requesting vehicle 102a and the destination 124, and the request may be generated by the preferential travel input device 148, the vehicle controller 228, and/or one or more other components of the vehicle system 202 at least partly in response to the input received from the passenger. Additionally, in some examples the request may include the unique identifier corresponding to the vehicle 102a from which the request is received (e.g., the requesting vehicle 102a).

At 806, the example method 800 may include accessing, with the computing device 160 and/or other components of the remote vehicle control system 154, road network data stored in, for example, a road network data store. The road network data may be based at least in part on a location of the vehicle 102a. In some examples, this may include global and/or local map data that may be stored and/or updated by the vehicle 102a and/or by the remote control center 156. Such road network data may include, among other things, data related to a global or local map of at least a portion of

the road network 104 at which the vehicle 102a is located. The road network data may include, for example, one or more maps illustrating the various roads 106 that may be available for the vehicle 102a to reach the destination 124 from the current location of the requesting vehicle 102a.

At 808, the example method 800 may include determining, at the computing device 160 and/or other components of the remote vehicle control system 154, a set of modified parameters for operating the requesting vehicle 102a as the requesting vehicle 102a travels within the road network 104 to the destination 124. For example, under normal operating conditions (e.g., non-preferential travel conditions), each of the vehicles 102 may be controlled by the respective vehicle controllers 228 to operate according to nominal operating parameters governing movement of the respective vehicles 102 within the road network 104. In some embodiments, the requesting vehicle 102a may be permitted and, in some situations, required to operate, within the road network 104, in accordance with a first set of nominal operating parameters, while a second vehicle 102b may be permitted and, in some situations, required to operate, within the road network 104, in accordance with a second set of nominal operating parameters. In some examples (e.g., in normal operating conditions), the first set of nominal operating parameters may be the same as the second set of nominal operating parameters, while in other examples the first set of nominal operating parameters may be different from the second set of nominal operating parameters. In any of the embodiments described herein, such sets of nominal operating parameters may include a speed threshold below which a respective one of the vehicles 102 may be permitted and, in some situations, required to operate, a drive line 146 along which the one of the vehicles 102 may be permitted and, in some situations, required to travel, a drive envelope 138 along which or within which the one of the vehicles 102 may be permitted and, in some situations, required to travel, traffic rules with which the one of the vehicles 102 must abide, and/or other rules or limitations for operating the one of the vehicles 102. In some examples, the first and second sets of nominal operating parameters may be generated and/or otherwise determined by the remote vehicle system 154, and may be provided to the respective vehicles 102a, 102b for operation thereof within the road network 104.

Accordingly, in examples in which the first vehicle 102a is operating in accordance with the first set of nominal operating parameters described above and in which the second vehicle 102b is operating in accordance with the second set of nominal operating parameters, at 808 the remote vehicle control system 154 may determine a third set of parameters (e.g., a set of one or more modified parameters) for operating the first vehicle 102a. The remote vehicle control system 154 may determine such a third set of parameters based at least partly on the request received at 804 and on the sensor data included in the sensor signals received at 802. Additionally, the third set of parameters determined at 808 may be at least partly less restrictive than the first set of nominal operating parameters governing normal operation of the first vehicle 102a. For example, where the first set of nominal operating parameters may define and/or otherwise include a first speed threshold below which the first vehicle 102a is permitted and/or required to operate, the third set of modified parameters determined at 808 may include a second speed threshold greater than the first speed threshold, thereby enabling the first vehicle 102a to travel at a higher speed. As another example, where the first set of nominal operating parameters may define and/or otherwise include a first strut setting, suspension setting,

brake pressure setting, turbo setting, engine tuning configuration, and/or other vehicle parameter associated with normal and/or non-preferential travel, the third set of modified parameters may define and/or otherwise include a second strut setting, suspension setting, brake pressure setting, turbo setting, engine tuning configuration, and/or other vehicle parameter setting causing the first vehicle **102a** to operate in a modified drive mode (e.g., a preferential travel mode, an emergency mode, etc.). In such a modified drive mode, the first vehicle **102a** may be caused to operate in accordance with preferences or other settings of one or more passengers riding in the first vehicle **102a**. For example, the first suspension setting of the first set of nominal operating parameters may cause a strut or other suspension component of the first vehicle **102a** to operate with a first level of sensitivity, and the second suspension setting of the third set of modified parameters may cause such a suspension component of the first vehicle **102a** to operate with a second level of sensitivity greater than the first level of sensitivity.

As a further example, and as illustrated in at least FIGS. **7a** and **7b**, where the first set of nominal operating parameters may be consumed by the path calculator **214** of the first vehicle **102a** to define and/or otherwise determine a first drive envelope **138a** (having a first drive envelope width **142a**) along which or within which the first vehicle **102a** is permitted and/or required to travel, the third set of modified parameters determined at **808** may be consumed by the path calculator **214** of the first vehicle **102a** to define and/or otherwise determine a fourth drive envelope **138d** (having a fourth drive envelope width **142d**) and/or a prioritized path **708** along which or within which the first vehicle **102a** is permitted and/or required to travel. In such examples, the fourth drive envelope width **142d** may be greater than the first drive envelope width **142a**, thereby expanding the area of the road **106** within which the first vehicle **102a** may travel in order to reach the destination **124**.

As noted above, the path calculator **214** of the first vehicle **102a** may determine the fourth drive envelope **138d** and/or the prioritized path **708** based at least partly on the set of parameters determined at **808**. Alternatively, in some examples, at **808** the computing device **160** and/or other components of the remote vehicle control system **154** may determine a prioritized path **708** extending from the first vehicle **102a** to the destination **124** based at least partly on the request received at **804** and on the road network data received at **806**. In any of the examples described herein, the first vehicle **102a** may be caused to travel along the prioritized path **708**, and the prioritized path **708** may be defined, at least in part, by the fourth drive envelope **138d** described above may include and/or define such a prioritized path **70**.

At **810**, the example method **800** may include determining, at the computing device **160** and/or other components of the remote vehicle control system **154**, one or more additional sets of modified parameters governing the operation of various remaining vehicles traversing the road network **104**. For example, as noted above the second vehicle **102b** may be caused to operate in accordance with a second set of nominal operating parameters. In such examples, at **810** the remote vehicle control system **154** may determine a fourth set of modified parameters for operating the second vehicle **102b**. The remote vehicle control system **154** may determine the fourth set of parameters based at least partly on the request received at **804** and on the sensor data included in the sensor signals received at **802**. Additionally, the fourth set of parameters determined at **810** may be at least partly more restrictive than the second set of parameters governing operation of the second vehicle **102b**.

For example, where the second set of nominal operating parameters may define and/or otherwise include a third speed threshold below which the second vehicle **102b** is permitted and/or required to operate, the fourth set of modified parameters determined at **810** may include a fourth speed threshold less than the third speed threshold, thereby requiring the second vehicle **102b** to travel at a lower speed. As another example, where the second set of nominal operating parameters may define and/or otherwise include a third strut setting, suspension setting, brake pressure setting, turbo setting, engine tuning configuration, and/or other vehicle parameter, the fourth set of modified parameters determined at **810** may define and/or otherwise include a fourth strut setting, suspension setting, brake pressure setting, turbo setting, engine tuning configuration, and/or other vehicle parameter setting causing the second vehicle **102b** to operate in a relatively more relaxed or refined drive mode. For example, the third suspension setting of the second set of nominal operating parameters may cause a strut or other suspension component of the second vehicle **102b** to operate with a third level of sensitivity, and the fourth suspension setting of the fourth set of modified parameters determined at **810** may cause such a suspension component of the second vehicle **102b** to operate with a fourth level of sensitivity less than the third level of sensitivity.

As a further example, and as illustrated in at least FIGS. **7a** and **7b**, where the second set of nominal operating parameters may be consumed by the path calculator **214** of the second vehicle **102b** to generate and/or otherwise determine a second drive envelope **138b** (having a second drive envelope width **142b**) along which or within which the second vehicle **102b** is permitted and/or required to travel, the fourth set of modified parameters determined at **810** may be consumed by the path calculator **214** of the second vehicle **102b** to generate and/or otherwise determine a fifth drive envelope **138e** (having a fifth drive envelope width **142e**) along which or within which the second vehicle **102b** is permitted and/or required to travel. In such examples, the fifth drive envelope width **142e** may be less than the second drive envelope width **142b**, thereby reducing the area of the road **106** within which the second vehicle **102b** may travel. In any of the examples described herein, the fourth set of parameters determined at **810** governing operation of the second vehicle **102b** may also be at least partly more restrictive than the third set of parameters determined at **808** governing preferential travel of the first vehicle **102a**.

As noted above, the path calculator **214** of the second vehicle **102b** may determine the fifth drive envelope **138e** based at least partly on the set of parameters determined at **810**. Alternatively, in some examples, the computing device **160** and/or other components of the remote vehicle control system **154** may determine one or more additional drive envelopes based at least partly on the request received at **804** and/or based at least partly on the road network data accessed at **806**. Example first, second, and third drive envelopes **138**, **406**, **408** are described above with respect to FIGS. **4a** and **4b**. Additionally, example first second, and third drive envelopes **138**, **506**, **508** are described above with respect to FIGS. **5a** and **5b**, and various drive envelopes are also described above with respect to FIGS. **6a**, **6b**, **7a**, and **7b**. In any of the examples described herein, a second and/or additional drive envelope determined at **810** may maintain a corresponding second vehicle **102b** and/or an additional one of the vehicles **102** outside of one or more trajectories (determined at **808**) defining the drive line **146** of the

requesting vehicle **102a** as the requesting vehicle **102a** travels to the particular destination **124** along a prioritized path.

At **812**, the example method **800** may include providing, with the computing device **160** and/or other components of the remote vehicle control system **154**, a first command signal to at least the requesting vehicle **102a**. For example, at **812** the computing device **160** may generate a first command signal including the set of modified parameters determined at **808**. As noted above, such a set of parameters may include information indicative of one or more trajectories, a drive line, a prioritized path, one or more drive envelopes, a speed threshold, a suspension setting, and/or other rules or vehicles operating parameters. At **812**, the computing device **160** may transfer, send, and/or otherwise provide the first command signal to the requesting vehicle **102a** via the network **152** and using, for example, the transmitter **306**. Additionally, the network interface **234** of the first vehicle **102a** may receive the first command signal at **812**, and the first command signal may cause the first vehicle **102a** to operate in accordance with the set of modified parameters determined at **808**. For example, the vehicle controller **228** may consume and/or otherwise process the first command signal received at **812**, and the path calculator **214** of the requesting vehicle **102a** may generate and/or otherwise determine a drive envelope defining, at least in part, a prioritized path extending from the requesting vehicle **102a** to the destination **124** based at least in part on the set of modified parameters included in the first command signal. The vehicle controller **228** of the requesting vehicle **102a** may also cause the requesting vehicle **102a** to travel along and/or within the drive envelope when traveling along the prioritized path. In traveling within the drive envelope, the vehicle controller **228** may, in some examples, cause the requesting vehicle **102a** to move from a first lane **110a** to a second lane **110b**, or vice versa. The vehicle controller **228** may also cause the requesting vehicle **102a** to make one or more turns, accelerate, decelerate, and/or perform one or more additional vehicle maneuvers in causing the requesting vehicle **102a** to travel within the drive envelope and/or along the prioritized path at **812**. Additionally or alternatively, causing the first vehicle **102a** to operate in accordance with the set of modified parameters included in the first command signal may cause the first vehicle **102a** to accelerate from a first speed to a second speed greater than a first speed. The first command signal provided at **812** may also cause a suspension component of the first vehicle **102a** to operate with an increased level of sensitivity. Further, the first command signal provided at **812** may cause the first vehicle **102a** to travel within an expanded drive envelope and/or to operate within an increased speed threshold.

At **814**, the example method **800** may include providing, with the computing device **160** and/or other components of the remote vehicle control system **154**, a second command signal to a second vehicle **102b** and/or to at least one of the remaining vehicles **102** traversing the road network **104**. For example, at **814** the computing device **160** may generate a second command signal including the set of modified parameters determined at **810**. Such a set of parameters may include information indicative of a path, drive envelope, speed threshold, suspension setting, and/or other rules or vehicle operating parameters. In some examples, the second command signal may also include information indicative of the one or more trajectories, drive line, drive envelope, prioritized path, and/or other modified parameters determined at **808**. In still further examples, the second command signal may also include additional information such as, for

example, the unique identifier associated with the requesting vehicle **102a**, unique identifiers associated with one or more of the remaining vehicles **102** traversing the road network **104**, weather conditions, road conditions, traffic conditions, and/or other parameters associated with the road network **104**. At **814**, the computing device **160** may transfer, send, and/or otherwise provide the second command signal to at least the second vehicle **102b** via the network **152** and using, for example, the transmitter **306**. In some examples, at **814** the computing device **160** may also transfer, send, and/or otherwise provide the second command signal to the requesting vehicle **102a** via the network **152**.

At **814**, the vehicle controller **228** of, for example, the second vehicle **102b** may receive the second command signal, and the second command signal may cause the second vehicle **102b** to operate in accordance with the set of modified parameters determined at **810**. For example, the vehicle controller **228** of the second vehicle **102b** may consume and/or otherwise process the second command signal received at **814**, and the path calculator **214** of the second vehicle **102b** may generate and/or otherwise determine a drive envelope **406** (FIG. **4b**) based at least partly on the set of modified parameters included in the second command signal. The vehicle controller **228** of the second vehicle **102b** may cause the second vehicle **102b** to travel within the drive envelope **406**. In traveling within the drive envelope **406**, the vehicle controller **228** of the second vehicle **102b** may, in some examples, cause the second vehicle **102b** to move from a first lane **110a** to a second lane **110b**, or vice versa. The vehicle controller **228** of the second vehicle **102b** may also cause the second vehicle **102b** to make one or more turns, accelerate, decelerate, and/or perform one or more additional vehicle maneuvers in causing the second vehicle **102b** to travel within the drive envelope. In particular, the vehicle controller **228** of the second vehicle **102b** may control the second vehicle **102b** to remain outside of one or more drive envelopes and/or trajectories (determined at **808**) defining the drive line **146** of the requesting vehicle **102a** as the requesting vehicle **102a** travels to the particular destination **124** along a prioritized path. Additionally or alternatively, causing the second vehicle **102b** to operate in accordance with the set of modified parameters included in the second command signal may cause the second vehicle **102b** to decelerate from a first speed to a second speed less than the first speed. Further, the second command signal provided at **814** may cause the second vehicle **102b** to travel within narrowed and/or otherwise reduced drive envelope and/or to operate within a reduced speed threshold.

At **814**, the method **800** may also include providing at least some of the information included in the various command signals via the preferential travel output device **150** of the respective vehicles **102**. For example, the vehicle controller **228** of the second vehicle **102b** may consume and/or otherwise process the second command signal received at **814**, and the vehicle controller **228** of the second vehicle **102b** may cause the display and/or other components of the preferential travel output device **150** to display at least part of the prioritized path (e.g., the prioritized path **604** illustrated in FIG. **6b**), the drive envelope (e.g., the fourth drive envelope **138d** illustrated in FIG. **7b**), the drive line (e.g., the drive line **146** illustrated in FIG. **5b**), one or more corresponding trajectories, and/or other parameters or sets of parameters. In such examples, the prioritized path **604** and/or the fourth drive envelope **138d** may be displayed on and/or with a map or other like illustration of the road **106**. In such examples, at least part of the road network **104**, the

destination **124**, and/or other portions of the environment **100** may also be displayed via the preferential travel output device **150**. Additionally or alternatively, at least one of the requesting vehicle **102a**, the second vehicle **102b**, the one or more remaining vehicles **102** traversing the road network **104**, an additional drive envelope (e.g., the drive envelope **710** illustrated in FIG. **7b**), the unique identifier and/or other information identifying at least one of the vehicles **102** (e.g., the requesting vehicle **102a**), and/or one or more of the modified parameters determined at **808** or **810** may also be displayed and/or otherwise provided. It is understood that such information provided by the preferential travel output device **150** may be updated in substantially real time and, the preferential travel output devices **150** in each of the respective vehicles **102** may provide similar and/or the same information.

In any of the examples described herein, the first, second, and/or corresponding additional command signals of the present disclosure may maintain the second vehicle **102b** and/or any of the additional vehicles **102** traversing the road network **104** outside of one or more drive envelopes and/or trajectories of the requesting vehicle **102a** as the requesting vehicle is traveling along a prioritized path to the destination **124**. As noted above, such trajectories may define a drive line **146** of the requesting vehicle **102a**, and the drive line **146** may be included in and/or may otherwise define a drive envelope **138** of the requesting vehicle **102a**. Such a drive envelope **138** may be included in and/or may define at least part of the prioritized path. In this way, the methods and systems of the present disclosure may be used to provide a requesting vehicle **102a** with a prioritized path that extends from the requesting vehicle **102a** to the destination **124**. As a result, the methods and systems of the present disclosure may enable passengers of vehicles (e.g., passengers of driverless vehicles) to travel to such a destination in an expedited manner in case of emergencies and/or other time-sensitive situations, and such methods and systems may improve passenger satisfaction. Such methods and systems may also result in reduced congestion or traffic in the road network **104** and may, thus, result in more efficient usage of the roads **106**, lanes **110**, and/or other portions of the road network **104**.

It should be appreciated that the subject matter presented herein may be implemented as a computer process, a computer-controlled apparatus, a computing system, or an article of manufacture, such as a computer-readable storage medium. While the subject matter described herein is presented in the general context of program modules that execute on one or more computing devices, those skilled in the art will recognize that other implementations may be performed in combination with other types of program modules. Generally, program modules include routines, programs, components, data structures, and other types of structures that perform particular tasks or implement particular abstract data types.

Those skilled in the art will also appreciate that aspects of the subject matter described herein may be practiced on or in conjunction with other computer system configurations beyond those described herein, including multiprocessor systems, microprocessor-based or programmable consumer electronics, minicomputers, mainframe computers, handheld computers, mobile telephone devices, tablet computing devices, special-purposed hardware devices, network appliances, and the like.

Although the subject matter presented herein has been described in language specific to computer structural features, methodological acts, and computer readable media, it

is to be understood that the invention defined in the appended claims is not necessarily limited to the specific features, acts, or media described herein. Rather, the specific features, acts, and media are disclosed as example forms of implementing the subject matter recited in the claims.

The subject matter described above is provided by way of illustration only and should not be construed as limiting. Furthermore, the claimed subject matter is not limited to implementations that solve any or all disadvantages noted in any part of this disclosure. Various modifications and changes may be made to the subject matter described herein without following the examples and applications illustrated and described, and without departing from the spirit and scope of the present invention, which is set forth in the following claims.

What is claimed is:

1. A method, comprising:

operating an autonomous vehicle in an environment in a first travel mode, the first travel mode associated with a first set of parameters;

sending, to a remote computing device via a network, a request for preferential travel from a location of the autonomous vehicle and information indicative of the location;

receiving a signal to operate the autonomous vehicle in a second travel mode, wherein the signal is determined based at least in part on the request, and wherein the second travel mode being associated with a second set of parameters different from the first set of parameters; and

operating the autonomous vehicle based at least in part on the second set of parameters.

2. The method of claim 1, wherein the first set of parameters or the second set of parameters comprises one or more of: a maximum speed, a trajectory, a drive line, or a set of traffic rules.

3. The method of claim 1, wherein operating the autonomous vehicle based at least in part on the second set of parameters comprises controlling the autonomous vehicle to at least one of:

move from a first road lane to a second road lane, or accelerate from a first speed to a second speed greater than the first speed.

4. The method of claim 1, further comprising causing, based at least in part on the request, an additional autonomous vehicle in the environment to receive a third set of parameters and to remain outside a path of the autonomous vehicle.

5. The method of claim 4, wherein the third set of parameters comprises one or more of a maximum speed, a trajectory, a drive line, or a set of traffic rules for the additional autonomous vehicle to follow in the environment.

6. The method of claim 1, wherein the request is generated in response to an input received from a passenger of the autonomous vehicle and via an input device.

7. The method of claim 1, wherein the second set of parameters is based at least in part on road network data associated with a current location of the autonomous vehicle, the road network data comprising one or more of:

an indication of a lane width,

a speed limit,

a traffic rule,

a traffic signal,

a road network, or

a map.

8. The method of claim 1, wherein at least one of:  
the first set of parameters includes at least one of a first  
speed limit and the second set of parameters includes at  
least one of a second speed limit which is different than  
the first speed limit,  
the first set of parameters includes a first suspension  
setting and the second set of parameters includes a  
second suspension setting that is different than the first  
suspension setting, or  
the first set of parameters includes a first path having a  
first path width and the second set of parameters  
includes a second path having a second path width that  
is different than the first path width.

9. A system comprising:  
one or more processors; and  
one or more non-transitory computer-readable media stor-  
ing instructions executable by the one or more proces-  
sors, wherein the instructions configure the system to:  
operate an autonomous vehicle in an environment in a  
first travel mode, the first travel mode associated  
with a first set of parameters;  
send, to a remote computing device via a network, a  
request for preferential travel from a location of the  
autonomous vehicle and information indicative of  
the location;  
receive a signal to operate the autonomous vehicle in a  
second travel mode, wherein the signal is determined  
based at least in part on the request, and wherein the  
second travel mode being associated with a second  
set of parameters different from the first set of  
parameters; and  
operate the autonomous vehicle based at least in part on  
the second set of parameters.

10. The system of claim 9, wherein the first set of  
parameters or the second set of parameters comprise one or  
more of: a speed limit, a drive envelope width, a set of traffic  
rules, or a suspension setting.

11. The system of claim 9, wherein the instructions further  
configure the system to receive an input from a passenger of  
the autonomous vehicle indicative of the request.

12. The system of claim 9, wherein:  
the first set of parameters includes a first suspension  
setting,  
the second set of parameters includes a second suspension  
setting different from the first suspension setting, and  
operating the autonomous vehicle based at least in part on  
the second set of parameters comprises operating a  
suspension component of the autonomous vehicle  
according to the second suspension setting.

13. The system of claim 9, wherein:  
the first set of parameters defines a first path having a first  
width, and  
the second set of parameters defines a second path having  
a second width different from the first width of the first  
path.

14. The system of claim 9, wherein the instructions further  
configure the system to:  
receive road network data corresponding to a current  
location of the autonomous vehicle, and  
wherein the second set of parameters is further based at  
least in part on the road network data and the road  
network data comprises one or more of:  
an indication of a lane width,  
a speed limit,  
a traffic rule,  
a traffic signal,

a road network, or  
a map.

15. The system of claim 9, wherein to operate the autono-  
mous vehicle based at least in part on the second set of  
parameters comprises controlling the autonomous vehicle to  
at least one of:  
move from a first road lane to a second road lane, or  
accelerate from a first speed to a second speed greater than  
the first speed.

16. The system of claim 9, wherein the instructions further  
configure the system to cause, based at least in part on the  
request, an additional autonomous vehicle in the environ-  
ment to receive a third set of parameters and to remain  
outside a path of the autonomous vehicle.

17. An autonomous vehicle in communication with a  
remote computing device via a network, the autonomous  
vehicle comprising:  
a network interface configured to:  
provide, to the remote computing device via the net-  
work, a request for preferential travel from a location  
of the autonomous vehicle and information indica-  
tive of the location; and  
receive a signal to operate the autonomous vehicle in a  
second travel mode, wherein the signal is determined  
based at least in part on the request; and  
a vehicle controller configured to:  
operate the autonomous vehicle in accordance with a  
first set of parameters associated with a first travel  
mode prior to the request for the second travel mode  
being provided; and  
operate the autonomous vehicle in accordance with a  
second set of parameters different from the first set of  
parameters based at least in part on the signal being  
received.

18. The autonomous vehicle of claim 17, wherein  
operating the autonomous vehicle in accordance with the  
first set of parameters causes the autonomous vehicle to  
travel within a first corridor of a road network, the first  
corridor having a first envelope width, and  
operating the autonomous vehicle in accordance with the  
second set of parameters by the vehicle controller  
causes the autonomous vehicle to travel within a sec-  
ond corridor of the road network, the second corridor  
having a second envelope width greater than the first  
envelope width.

19. The autonomous vehicle of claim 17, wherein:  
the first set of parameters specifies a first region in which  
the vehicle controller is permitted to control the autono-  
mous vehicle to operate,  
the second set of parameters specifies a second region in  
which the vehicle controller is permitted to control the  
autonomous vehicle to operate,  
the second region being different than the first region, and  
the first set of parameters or the second set of parameters  
comprise one or more of a speed limit, a set of traffic  
rules, a suspension setting, or a drive envelope width.

20. The autonomous vehicle of claim 17, wherein oper-  
ating the autonomous vehicle in accordance with the second  
set of parameters causes the autonomous vehicle to at least  
one of:  
move from a first road lane to a second road lane different  
from the first road lane,  
accelerate from a first speed to a second speed greater than  
the first speed, or  
adjust a suspension of the autonomous vehicle.